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Cooperative surveillance of unknown environmental boundaries by multiple nonholonomic robots

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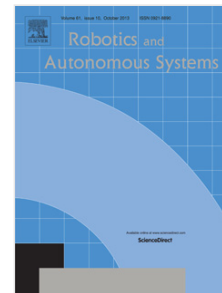
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- We consider several anonymous non-communicating Dubins-car like robots in a plane.
- Every robot has a point-wise access to the value of an unknown environmental field.
- A new decentralized navigation strategy is proposed.
- All robots are driven to the isoline where the field assumes a pre-specified value.
- Inter-robots collisions and getting into clusters are excluded.

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