Rapidly Exploring Random Tree

Brett Wayne Millar

Autonomous Vehicle Andrzej Zak,2016-09-07 Autonomous vehicles, despite their relatively short history, have already found practical application in many areas of human activity. Such vehicles are usually replacing people in performing tasks that require long operating time and are held in inaccessible or hazardous environments. Nevertheless, autonomous robotics is probably the area that is being developed the most because of the great demand for such devices in different areas of our lives. This book is a collection of experiences shared by scientists from different parts of the world doing researches and daily exploiting autonomous systems. Giving this book in the hands of the reader, we hope that it will be a treasure trove of knowledge and inspiration for further research in the field of autonomous vehicles.

The Future of Artificial Intelligence and Robotics David Pastor-Escuredo, Imene Brigui, Nishtha Kesswani, Sushanta Bordoloi, Ashok Kumar Ray, 2024-08-19 This book includes the results from the 5th International Conference on Deep Learning, Artificial Intelligence and Robotics (ICDLAIR), held in National Institute of Technology, Kurukshetra, on December 07-09, 2023, which brought together visionaries, researchers, and industry leaders at the forefront of technological innovation. In the rapidly evolving landscape of technology, deep learning, artificial intelligence, and robotics stand as a beacon of innovation and intellectual exchange. Among the myriad of groundbreaking contributions, a notable gem emerges—a forthcoming book that promises to encapsulate the essence of the 5th International Conference on Deep Learning, Artificial Intelligence and Robotics, (ICDLAIR) 2023 proceedings. Titled Progress in AI-Driven Business Decisions & Robotic Process Automation, this publication is poised to become a cornerstone for enthusiasts, researchers, and professionals seeking a comprehensive understanding of the latest advancements in deep learning, artificial intelligence, and robotics. Focused on the theme Progress in AI-Driven Business Decisions & Robotic Process Automation, the conference showcased groundbreaking developments in the field, exploring the intersection of deep learning, artificial intelligence (AI), and robotics.

ROBOTICS ENGINEERING PRABHU TL, Embark on an exhilarating journey into the realm of robotics engineering—an exploration of cutting-edge technologies, design principles, and groundbreaking innovations that are shaping the future of automation. Unveiling the Future: Exploring Robotics Engineering and Innovation is a comprehensive guide that unveils the principles and practices that empower individuals to understand, create, and revolutionize robotics technology. Pioneering

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Robotics Research Tamim Asfour, Eiichi Yoshida, Jaeheung Park, Henrik Christensen, Oussama Khatib, 2022-02-17 This book contains the papers that were presented at the 17th International Symposium of Robotics Research (ISRR). The ISRR promotes the development and dissemination of groundbreaking research and technological innovation in robotics useful to society by providing a lively, intimate, forward-looking forum for discussion and debate about the current status and future trends of robotics with great emphasis on its potential role to benefit humankind. The symposium contributions contained in this book report on a variety of new robotics research results covering a broad spectrum organized into the categories: design, control; grasping and manipulation, planning, robot vision, and robot learning.

Robot Intelligence Technology and Applications 7 Jun Jo, Han-Lim Choi, Marde Helbig, Hyondong Oh, Jemin

Hwangbo, Chang-Hun Lee, Bela Stantic, 2023-02-28 We are starting to enter a post-COVID-19 life. While this pandemic has made everyone's life challenging, it also expedited the transition of our everyday lives into a new form, often called "The New Normal." Although many people often use the terminology, perhaps we still do not have consensus about what it is and what it should be like. However, one thing that is clear namely that robotics and artificial intelligence technologies are playing a critical role in this transition phase of our everyday lives. We saw the emergence of last-mile delivery robots on the street, AIembedded service robots in restaurants, uninhabited shops, non-face-to-face medical services, conferences and talks in metaverses, and AI-based online education programs. This book is an edition that aims at serving researchers and practitioners in related fields with a timely dissemination of the recent progress in the areas of robotics and artificial intelligence. This book is based on a collection of papers presented at the 10th International Conference on Robot Intelligence Technology and Applications (RiTA), held at Griffith University in the Gold Coast, Queensland, Australia. The conference was held in a hybrid format on December 7-9, 2022, with the main theme "Artificial, Agile, Acute Robot Intelligence." For better readability, the total of 41 papers are grouped into five chapters: Chapter I: Motion Planning and Control; Chapter II: Vision and Image Processing; Chapter III: Unmanned Aerial Vehicles and Autonomous Vehicles; Chapter IV: Learning and Classification; and Chapter V: Environmental and Societal Robotic Applications. The articles were accepted through a rigorous peer-review process and presented at the RiTA 2022 conference. Also, they were updated, and final versions of the manuscripts were produced after in-depth discussions during the conference. We would like to thank all the authors and editors for contributing to this edition.

Information-rich Path Planning Under General Constraints Using Rapidly-exploring Random Trees Daniel S. Levine (Ph. D.), Massachusetts Institute of Technology. Department of Aeronautics and Astronautics, 2010 This thesis introduces the Information-rich Rapidly-exploring Random Tree (IRRT), an extension of the RRT algorithm that embeds information collection as predicted using Fisher information matrices. The primary contribution of this trajectory generation algorithm is target-based information maximization in general (possibly heavily constrained) environments, with complex vehicle dynamic constraints and sensor limitations, including limited resolution and narrow field-of-view. Extensions of IRRT both for decentralized, multiagent missions and for information-rich planning with multimodal distributions are presented. IRRT is distinguished from previous solution strategies by its computational tractability and general constraint characterization. A progression of simulation results demonstrates that this implementation can generate complex target-tracking behaviors from a simple model of the trade-off between information gathering and goal arrival.

On-Road Intelligent Vehicles Rahul Kala,2016-04-27 On-Road Intelligent Vehicles: Motion Planning for Intelligent Transportation Systems deals with the technology of autonomous vehicles, with a special focus on the navigation and planning aspects, presenting the information in three parts. Part One deals with the use of different sensors to perceive the

environment, thereafter mapping the multi-domain senses to make a map of the operational scenario, including topics such as proximity sensors which give distances to obstacles, vision cameras, and computer vision techniques that may be used to pre-process the image, extract relevant features, and use classification techniques like neural networks and support vector machines for the identification of roads, lanes, vehicles, obstacles, traffic lights, signs, and pedestrians. With a detailed insight into the technology behind the vehicle, Part Two of the book focuses on the problem of motion planning. Numerous planning techniques are discussed and adapted to work for multi-vehicle traffic scenarios, including the use of sampling based approaches comprised of Genetic Algorithm and Rapidly-exploring Random Trees and Graph search based approaches, including a hierarchical decomposition of the algorithm and heuristic selection of nodes for limited exploration, Reactive Planning based approaches, including Fuzzy based planning, Potential Field based planning, and Elastic Strip and logic based planning. Part Three of the book covers the macroscopic concepts related to Intelligent Transportation Systems with a discussion of various topics and concepts related to transportation systems, including a description of traffic flow, the basic theory behind transportation systems, and generation of shock waves. - Provides an overall coverage of autonomous vehicles and Intelligent Transportation Systems - Presents a detailed overview, followed by the challenging problems of navigation and planning - Teaches how to compare, contrast, and differentiate navigation algorithms

Rapidly-exploring Random Tree Inspired Multi-robot Space Coverage Asish Ghoshal,2012 Inspired by the Rapidly-exploring Random Tree (RRT) data-structure and algorithm for path planning, we introduce an approach for spanning physical space with a group of simple mobile robots. Emphasizing minimalism and using only InfraRed and contact sensors for communication, our position unaware robots physically embody elements of the tree. Although robots are fundamentally constrained in the spatial operations they may perform, we show that the approach -implemented on physical robots- remains consistent with the original data-structure idea. In particular, we show that a generalized form of Voronoi bias is present in the construction of the tree, and that such trees have an approximate space-filling property. We present an analysis of the physical system via sets of coupled stochastic equations: the first being the rate-equation for the transitions made by the robot controllers, and the second to capture the spatial process describing tree formation. We also introduce a class of fixed edge length RRTs called IRRT and show that IRRT s have similar space-filling properties to that of RRTs. We are able to provide an understanding of the control parameters in terms of a process mixing-time and show the dependence of the Voronoi bias on an interference parameter which grows as O*sqrt(N).

Single-Query Robot Motion Planning Using Rapidly Exploring Random Trees (RRTs). Jonathan Bagot, 2014 Robots moving about in complex environments must be capable of determining and performing difficult motion sequences to accomplish tasks. As the tasks become more complicated, robots with greater dexterity are required. An increase in the number of degrees of freedom and a desire for autonomy in uncertain environments with real-time requirements leaves much room for

improvement in the current popular robot motion planning algorithms. In this thesis, state of the art robot motion planning techniques are surveyed. A solution to the general movers problem in the context of motion planning for robots is presented. The proposed robot motion planner solves the general movers problem using a sample-based tree planner combined with an incremental simulator. The robot motion planner is demonstrated both in simulation and the real world. Experiments are conducted and the results analyzed. Based on the results, methods for tuning the robot motion planner to improve the performance are proposed.

Proceedings 2003 IEEE/RSJ International Conference on Intelligent Robots and Systems ,2003

<u>Mechatronics and Applied Mechanics II</u> Ching Kuo Wang, Jing Guo, 2013-02-13 Selected, peer reviewed papers from the 2nd International Conference on Mechatronics and Applied Mechanics (ICMAM 2012), December 6 – 7, 2012, Honkong, December 8-9, 2012, Taipei

Intelligent Autonomous Vehicles 2004 (IAV 2004) J. Santos-Victor, M. I. Ribeiro, 2005

Robotics: Science and Systems I Sebastian Thrun,2005 Robotics: Science and Systems II spans all areas of robotics, bringing togetherresearchers working on the algorithmic and mathematical foundations of robotics, roboticsapplications, and analysis of robotics systems. This volume presents the proceedings of the secondannual Robotics: Science and Systems conference, held in August 2006. Papers report state-of-the-artresearch on topics as diverse as Legged Robotics, Reconfigurable Robots, Biomimetic Robots, Manipulation, Humanoid Robotics, Telerobotics, Haptics, Motion Planning, Collision Avoidance, RobotVision and Perception, Bayesian Techniques, Machine Learning, Mobile Robots, and Multirobotsystems.

Advanced Research on Applied Mechanics and Manufacturing System Helen Zhang, David Jin, X.J. Zhao, 2012-12-13 Selected, peer reviewed papers from the 2012 International Conference on Applied Mechanics and Manufacturing System (AMMS 2012), November 24-25, 2012, Guangzhou, China

Hybrid Systems : Computation and Control ,2004

Multi-resolution Obstacle Mapping with Rapidly-exploring Random Tree Path Planning for Unmanned Air Vehicles Brett Wayne Millar,2011 Unmanned air vehicles (UAVs) have become an important area of research. UAVs are used in many environments which may have previously unknown obstacles or sources of danger. This research addresses the problem of obstacle mapping and path planning while the UAV is in flight. Online obstacle mapping is achieved through the use of a multi-resolution map. As sensor information is received, a quadtree is built up to hold the information based upon the uncertainty associated with the measurement. Once a quadtree map of obstacles is built up, we desire online path replanning to occur as quickly as possible. We introduce the idea of a quadtree rapidly-exploring random tree (RRT), which will be used as the online path re-planning algorithm. This approach implements a variable sized step instead of the fixed-step

size usually used in the RRT algorithm. This variable step uses the structure of the quadtree to determine the step size. The step size grows larger or smaller based upon the size of the area represented by the quadtree it passes through. Finally this approach is tested in a simulation environment. The results show that the quadtree RRT requires fewer steps on average than a standard RRT to find a path through an area. It also has a smaller variance in the number of steps taken by the path planning algorithm in comparison to the standard RRT.

Development of Miniature Climbing Robots Jizhong Xiao, 2002

Proceedings 2002 IEEE/RSJ International Conference on Intelligent Robots and Systems ,2002

Advances in Intelligent and Autonomous Aerospace Systems John Valasek,2012 Research advances in embedded computational intelligence, communication, control, and new mechanisms for sensing, actuation, and adaptation hold the promise to transform aerospace. The result will be air and space vehicles, propulsion systems, exploration systems, and vehicle management systems that respond more quickly, provide large-scale distributed coordination, work in dangerous or inaccessible environments, and augment human capabilities. Advances in Intelligent and Autonomous Aerospace Systems seeks to provide both the aerospace researcher and the practicing aerospace engineer with an exposition on the latest innovative methods and approaches that focus on intelligent and autonomous aerospace systems. The chapters are written by leading researchers in this field, and include ideas, directions, and recent results on intelligent aerospace research issues with a focus on dynamics and control, systems engineering, and aerospace design. The content on uncertainties, modeling of large and highly non-linear complex systems, robustness, and adaptivity is intended to be useful in both the sub-system and the overall system level design and analysis of various aerospace vehicles. A broad spectrum of methods and approaches are presented, including: * Bio-Inspiration * Fuzzy Logic * Genetic Algorithms * Q-Learning * Markov Decision Processes * Approximate Dynamic Programming * Artificial Neural Networks * Probabilistic Maps * Multi-Agent Systems * Kalman, particle, and confidence filtering

Design of a Path-planner for a Biomass Production Servicing Robotic System Ernst Schermann, 2005

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