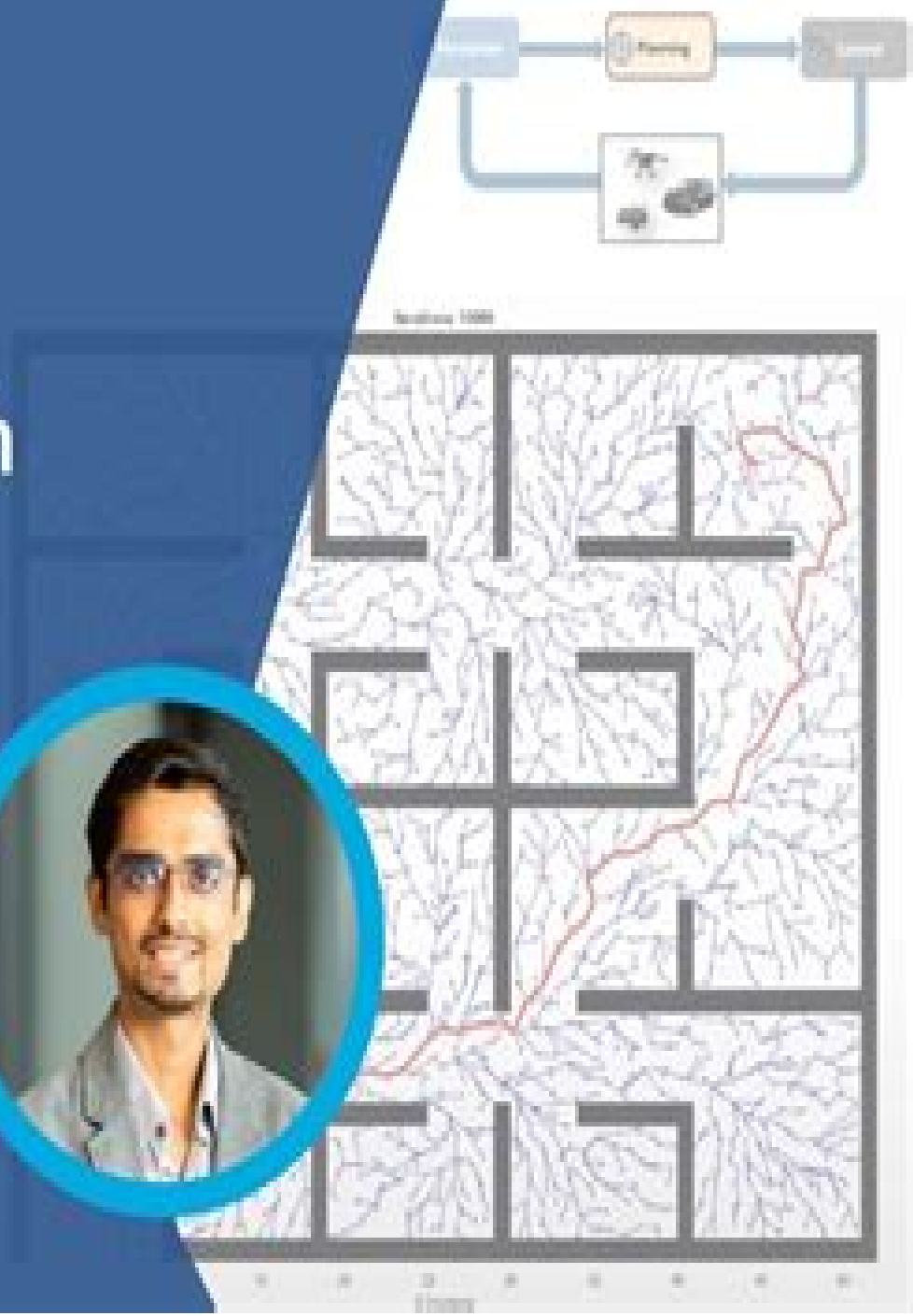
Robotics

Motion Planning with the RRT Algorithm

Introduction to Motion Planning Algorithms

PART 1



Planning Algorithms Motion Planning

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Planning Algorithms Motion Planning:

Planning Algorithms Steven M. LaValle,2006-05-29 Planning algorithms are impacting technical disciplines and industries around the world including robotics computer aided design manufacturing computer graphics aerospace applications drug design and protein folding This coherent and comprehensive book unifies material from several sources including robotics control theory artificial intelligence and algorithms The treatment is centered on robot motion planning but integrates material on planning in discrete spaces A major part of the book is devoted to planning under uncertainty including decision theory Markov decision processes and information spaces which are the configuration spaces of all sensor based planning problems The last part of the book delves into planning under differential constraints that arise when automating the motions of virtually any mechanical system This text and reference is intended for students engineers and researchers in robotics artificial intelligence and control theory as well as computer graphics algorithms and computational biology *Motion Planning in Medicine: Optimization and Simulation Algorithms for Image-Guided Procedures* Ron Alterovitz,Ken Goldberg,2008-09-20 Written by Ron Alterovitz and Ken Goldberg this monograph combines ideas from robotics physically based modeling and operations research to develop new motion planning and optimization algorithms for image guided medical procedures *Motion planning and feedback control techniques with applications to long tractor-trailer vehicles* Oskar Ljungqvist,2020-04-20 During the last decades improved sensor and hardware technologies as well as new methods and algorithms have made self driving vehicles a realistic possibility in the near future At the same time there has been a growing demand within the transportation sector to increase efficiency and to reduce the environmental impact related to transportation of people and goods Therefore many leading automotive and technology companies have turned their attention towards developing advanced driver assistance systems and self driving vehicles Autonomous vehicles are expected to have their first big impact in closed environments such as mines harbors loading and offloading sites In such areas the legal requirements are less restrictive and the surrounding environment is more controlled and predictable compared to urban areas Expected positive outcomes include increased productivity and safety reduced emissions and the possibility to relieve the human from performing complex or dangerous tasks Within these sites tractor trailer vehicles are frequently used for transportation These vehicles are composed of several interconnected vehicle segments and are therefore large complex and unstable while reversing This thesis addresses the problem of designing efficient motion planning and feedback control techniques for such systems The contributions of this thesis are within the area of motion planning and feedback control for long tractor trailer combinations operating at low speeds in closed and unstructured environments It includes development of motion planning and feedback control frameworks structured design tools for guaranteeing closed loop stability and experimental validation of the proposed solutions through simulations lab and field experiments Even though the primary application in this work is tractor trailer vehicles many of the proposed approaches can with some

adjustments also be used for other systems such as drones and ships The developed sampling based motion planning algorithms are based upon the probabilistic closed loop rapidly exploring random tree CL RRT algorithm and the deterministic lattice based motion planning algorithm It is also proposed to use numerical optimal control offline for precomputing libraries of optimized maneuvers as well as during online planning in the form of a warm started optimization step To follow the motion plan several predictive path following control approaches are proposed with different computational complexity and performance Common for these approaches are that they use a path following error model of the vehicle for future predictions and are tailored to operate in series with a motion planner that computes feasible paths The design strategies for the path following approaches include linear quadratic LQ control and several advanced model predictive control MPC techniques to account for physical and sensing limitations To strengthen the practical value of the developed techniques several of the proposed approaches have been implemented and successfully demonstrated in field experiments on a full scale test platform To estimate the vehicle states needed for control a novel nonlinear observer is evaluated on the full scale test vehicle It is designed to only utilize information from sensors that are mounted on the tractor making the system independent of any sensor mounted on the trailer Under de senaste rtiondena har utvecklingen av sensor och h rdvaruteknik g tt i en snabb takt samtidigt som nya metoder och algoritmer har introducerats Samtidigt st lls det stora krav p transportsektorn att ka effektiviteten och minska milj p verkan vid transporter av b de m nniskor och varor Som en f ljd av detta har m nga ledande fordonstillverkare och teknikf retag b rjat satsat p att utveckla avancerade f rarst dsystem och sj lvk rande fordon ven forskningen inom autonoma fordon har under de senaste rtiondena kraftig kat d en rad tekniska problem terst r att l sas F rarl sa fordon f rv ntas f sitt f rsta stora genombrott i slutna milj er s som gruvor hamnar lastnings och lossningsplatser I s dana omr den r lagstiftningen mindre h rd j mf rt med stadsomr den och omgivningen r mer kontrollerad och f ruts gbar N gra av de f rv ntade positiva effekterna r kad produktivitet och s kerhet minskade utsl pp och m jligheten att avlasta m nniskor fr n att utf ra sv ra eller farliga uppgifter Inom dessa platser anv nds ofta lastbilar med olika sl pvagnskombinationer f r att transportera material En s dan fordonskombination r uppbyggd av flera ihopkopplade moduler och r s ledes utmanande att backa d systemet r instabilt Detta g r det sv rt att utforma ramverk f r att styra s dana system vid exempelvis autonom backning Sj lvk rande fordon r mycket komplexa system som best r av en rad olika komponenter vilka r designade f r att l sa separata delproblem Tv viktiga komponenter i ett sj lvk rande fordon r dels r relseplaneraren som har i uppgift att planera hur fordonet ska r ra sig f r att p ett s kert s tt n ett verordnat m l och dels den banf ljande regulatorn vars uppgift r att se till att den planerade man vern faktiskt utf rs i praktiken trots st rningar och modellfel I denna avhandling presenteras flera olika algoritmer f r att planera och utf ra komplexa man vrar f r lastbilar med olika typer av sl pvagnskombinationer De presenterade algoritmerna r avsedda att anv ndas som avancerade f rarst dsystem eller som komponenter i ett helt autonomt system ven om den prim ra applikationen i denna avhandling r lastbilar med sl p kan m nga

av de f rslagna algoritmerna ven anv ndas f r en rad andra system s som dr nare och b tar Experimentell validering r viktigt f r att motivera att en f reslagen algoritm r anv ndbar i praktiken I denna avhandling har flera av de f reslagna planerings och reglerstrategierna implementerats p en sm skalig testplattform och utv rderats i en kontrollerad labbmilj Ut ver detta har ven flera av de f reslagna ramverken implementerats och utv rderats i f ltexperiment p en fullskalig test plattform som har utvecklats i samarbete med Scania CV H r utv rderas ven en ny metod f r att skatta sl pvagnens beteende genom att endast utnyttja information fr n sensorer monterade p lastbilen vilket g r det f reslagna ramverket oberoende av sensorer monterade p sl pvagnen Optimized-Motion Planning Cherif Ahrikencheikh,Ali A. Seireg,1994-10-14 The first handbook to the practical specifics of motion planning Optimized Motion Planning offers design engineers methods and insights for solving real motion planning problems in a 3 dimensional space Complete with a disk of software programs this unique guide allows users to design test and implement possible solutions useful in a host of contexts especially tool path planning Beginning with a brief overview of the general class of problems examined within the book as well as available solution techniques Part 1 familiarizes the reader with the conceptual threads that underlie each approach This early discussion also considers the specific applications of each technique as well as its computational efficiency Part 2 illustrates basic problem solving methodology by considering the case of a point moving between stationary polygons in a plane This section features algorithms for data organization and storage the concepts of passage networks and feasibility charts as well as the path optimization algorithm Elaborating on the problematic model described in Part 2 Part 3 develops an algorithm for optimizing the motion of a point between stationary polyhedra in a 3 dimensional space This algorithm is first applied to the case of nonpoint objects moving between obstacles that can be stationary or moving with known patterns It s then used in connection with the extensively investigated problem of motion planning for multilink manipulators Key Elements for Motion Planning Algorithms Antonio Benitez,2010 Key Elements for Motion Planning Algorithms **Statistical Analysis of Sensor-based Motion Planning Algorithms** Vladimir Yegorov,1996 **Robotics Text Book** Manish Soni,2024-11-13 Welcome to Robotics From Fundamentals to Advanced Applications your comprehensive guide to understanding and mastering the field of robotics In an era where automation and intelligent systems are revolutionizing industries robotics stands at the forefront driving innovations across manufacturing healthcare exploration and more As we delve deeper into this transformative technology it is essential for both beginners and seasoned professionals to grasp its fundamental concepts and applications thoroughly This book is meticulously crafted to serve as a complete learning resource catering to the diverse needs of learners at all levels Whether you are a student embarking on your first exploration into robotics or a professional seeking to enhance your expertise this guide provides the essential tools and resources necessary to achieve your learning goals **Robotic Mechanical Systems Fundamentals** Shridhar Shastri,2025-02-20 Robotic Mechanical Systems Fundamentals serves as a comprehensive guide to understanding the core principles and technological intricacies of

robotic systems in today s rapidly evolving landscape We offer an in depth exploration of the mechanical foundations that drive the design control and functionality of robots making it an essential resource for students researchers and industry professionals Our journey begins with a thorough examination of the fundamental concepts and historical developments that shape robotics Readers will gain insights into the dynamics of robotic systems through the Newton Euler equations paving the way for a deeper understanding of the Lagrange formulation which offers a powerful framework for analyzing robot motion Focusing on dynamic modeling we provide a detailed look at the mechanisms governing the behavior of manipulators emphasizing the complexities involved in designing and controlling robotic arms Additionally we address control forces and torques highlighting strategies to ensure precision and efficiency in robotic actions With a holistic approach that considers the ethical and societal implications of robotics Robotic Mechanical Systems Fundamentals balances theoretical foundations with practical applications making it accessible for beginners and valuable for seasoned professionals Authored by experts our book equips readers to navigate the fascinating world of robotics inspiring a deeper appreciation for the technologies that shape our future *Automatic Control, Robotics, and Information Processing* Piotr Kulczycki,Józef Korbicz,Janusz Kacprzyk,2020-09-03 This book presents a wide and comprehensive range of issues and problems in various fields of science and engineering from both theoretical and applied perspectives The desire to develop more effective and efficient tools and techniques for dealing with complex processes and systems has been a natural inspiration for the emergence of numerous fields of science and technology in particular control and automation and more recently robotics The contributions gathered here concern the development of methods and algorithms to determine best practices regarding broadly perceived decisions or controls From an engineering standpoint many of them focus on how to automate a specific process or complex system From a tools based perspective several contributions address the development of analytic and algorithmic methods and techniques devices and systems that make it possible to develop and subsequently implement the automation and robotization of crucial areas of human activity All topics discussed are illustrated with sample applications **Parallel Search Algorithms for Robot Motion Planning** Daniel Joseph Challou,1995 *Implementation and Experimentation with Motion Planning Algorithms* ,1990 The main charter of this contract is the implementation and experimentation with motion planning algorithms that emphasize the exact combinatorial and purely geometric approach Motion planning is considered to be one of the major research areas in robotics and is one of the main stages in the design and implementation of autonomous intelligent systems which is an important long range goal in robotics research Motion planning is one of the basic capabilities that such a system must possess In purely geometric terms the simplest version of the problem can be stated as follows The system is given complete information about the geometry of the environment in which it is to operate and of its own structure and has to process it so that when commanded to move from its current position to some target position it can determine whether it can do so without colliding with any of the obstacles around it and if so plan and execute such a motion These are

many variants of the problem A few of those are motion planning in environments that are only partially known to the system compliant motion planning that allows contact with obstacles which might be unavoidable due to measurement errors optimal motion planning motion planning with kino dynamic constraints and motion planning amidst moving obstacles Still even the simplest static and purely geometric version stated above is far from being simple and poses serious challenges in the design of efficient and robust algorithms Engineering Autonomous Vehicles and Robots Shaoshan Liu,2020-03-04 Offers a step by step guide to building autonomous vehicles and robots with source code and accompanying videos The first book of its kind on the detailed steps for creating an autonomous vehicle or robot this book provides an overview of the technology and introduction of the key elements involved in developing autonomous vehicles and offers an excellent introduction to the basics for someone new to the topic of autonomous vehicles and the innovative modular based engineering approach called DragonFly Engineering Autonomous Vehicles and Robots The DragonFly Modular based Approach covers everything that technical professionals need to know about CAN bus chassis sonars radars GNSS computer vision localization perception motion planning and more Particularly it covers Computer Vision for active perception and localization as well as mapping and motion planning The book offers several case studies on the building of an autonomous passenger pod bus and vending robot It features a large amount of supplementary material including the standard protocol and sample codes for chassis sonar and radar GPSD protocol NMEA protocol and GPS deployment methods are also provided Most importantly readers will learn the philosophy behind the DragonFly modular based design approach which empowers readers to design and build their own autonomous vehicles and robots with flexibility and affordability Offers progressive guidance on building autonomous vehicles and robots Provides detailed steps and codes to create an autonomous machine at affordable cost and with a modular approach Written by one of the pioneers in the field building autonomous vehicles Includes case studies source code and state of the art research results Accompanied by a website with supplementary material including sample code for chassis sonar radar GPS deployment methods Vision Calibration methods Engineering Autonomous Vehicles and Robots is an excellent book for students researchers and practitioners in the field of autonomous vehicles and robots **Exploiting Direct Optimal Control for Motion Planning in Unstructured Environments** Kristoffer Bergman,2021-03-16 During the last decades motion planning for autonomous systems has become an important area of research The high interest is not the least due to the development of systems such as self driving cars unmanned aerial vehicles and robotic manipulators The objective in optimal motion planning problems is to find feasible motion plans that also optimize a performance measure From a control perspective the problem is an instance of an optimal control problem This thesis addresses optimal motion planning problems for complex dynamical systems that operate in unstructured environments where no prior reference such as road lane information is available Some example scenarios are autonomous docking of vessels in harbors and autonomous parking of self driving tractor trailer vehicles at loading sites The

focus is to develop optimal motion planning algorithms that can reliably be applied to these types of problems This is achieved by combining recent ideas from automatic control numerical optimization and robotics The first contribution is a systematic approach for computing local solutions to motion planning problems in challenging unstructured environments The solutions are computed by combining homotopy methods and direct optimal control techniques The general principle is to define a homotopy that transforms or preferably relaxes the original problem to an easily solved problem The approach is demonstrated in motion planning problems in 2D and 3D environments where the presented method outperforms a state of the art asymptotically optimal motion planner based on random sampling The second contribution is an optimization based framework for automatic generation of motion primitives for lattice based motion planners Given a family of systems the user only needs to specify which principle types of motions that are relevant for the considered system family Based on the selected principle motions and a selected system instance the framework computes a library of motion primitives by simultaneously optimizing the motions and the terminal states The final contribution of this thesis is a motion planning framework that combines the strengths of sampling based planners with direct optimal control in a novel way The sampling based planner is applied to the problem in a first step using a discretized search space where the system dynamics and objective function are chosen to coincide with those used in a second step based on optimal control This combination ensures that the sampling based motion planner provides a feasible motion plan which is highly suitable as warm start to the optimal control step Furthermore the second step is modified such that it also can be applied in a receding horizon fashion where the proposed combination of methods is used to provide theoretical guarantees in terms of recursive feasibility worst case objective function value and convergence to the terminal state The proposed motion planning framework is successfully applied to several problems in challenging unstructured environments for tractor trailer vehicles The framework is also applied and tailored for maritime navigation for vessels in archipelagos and harbors where it is able to compute energy efficient trajectories which complies with the international regulations for preventing collisions at sea **Planning and Optimization Algorithms for Image-guided Medical Procedures** Ron Alterovitz,2006 **Connectionist Robot Motion Planning** Bartlett Mel,1990-08-28 Connectionist Robot Motion Planning A Neurally Inspired Approach to Visually Guided Reaching is the third series in a cluster of books on robotics and related areas as part of the Perspectives in Artificial Intelligence Series This series focuses on an experimental paradigm using the MURPHY system to tackle critical issues surrounding robot motion planning MURPHY is a robot camera system developed to explore an approach to the kinematics of sensory motor learning and control for a multi link arm Organized into eight chapters this book describes the guiding of a multi link arm to visual targets in a cluttered workspace It primarily focuses on ecological solutions that are relevant to the typical visually guided reaching behaviors of humans and animals in natural environments Algorithms that work well in unmodeled workspaces whose effective layouts can change from moment to moment with movements of the eyes head limbs

and body are also presented This book also examines the strengths of neurally inspired connectionist representations and the utility of heuristic search when good performance even if suboptimal is adequate for the task The co evolution of MURPHY s design with the brain presumably in response to similar computational pressures is described in the concluding chapters specifically presenting the division of labor between programmed feedforward and visual feedback modes of limb control Design engineers in the fields of biology neurophysiology and cognitive psychology will find this book of great value

Robot Motion Planning Jean-Claude Latombe,2012-12-06 One of the ultimate goals in Robotics is to create autonomous robots Such robots will accept high level descriptions of tasks and will execute them without further human intervention The input descriptions will specify what the user wants done rather than how to do it The robots will be any kind of versatile mechanical device equipped with actuators and sensors under the control of a computing system Making progress toward autonomous robots is of major practical inter est in a wide variety of application domains including manufacturing construction waste management space exploration undersea work as sistance for the disabled and medical surgery It is also of great technical interest especially for Computer Science because it raises challenging and rich computational issues from which new concepts of broad useful ness are likely to emerge Developing the technologies necessary for autonomous robots is a formidable undertaking with deep interweaved ramifications in auto mated reasoning perception and control It raises many important prob lems One of them motion planning is the central theme of this book It can be loosely stated as follows How can a robot decide what motions to perform in order to achieve goal arrangements of physical objects This capability is eminently necessary since by definition a robot accomplishes tasks by moving in the real world The minimum one would expect from an autonomous robot is the ability to plan its x Preface own motions **Computational Geometry for Multiple-robot Motion Planning** Susan Elizabeth Hert,1997 **Efficient Motion Planning Algorithms in Environments of Bounded Local Complexity** Courant Institute of Mathematical Sciences. Computer Science Department,J. T. Schwartz,M. Sharir,1985 *Practical Motion Planning in Robotics* Kamal Gupta,Angel P. del Pobil,1998-10-15 Practical Motion Planning in Robotics Current Approaches and Future Directions Edited by Kamal Gupta Simon Fraser University Burnaby Canada Angel P del Pobil Jaume l University Castellon Spain Designed to bridge the gap between research and industry Practical Motion Planning in Robotics brings theoretical advances to bear on real world applications Capitalizing on recent progress this comprehensive study emphasizes the practical aspects of techniques for collision detection obstacle avoidance path planning and manipulation planning The broad approach spans both model and sensor based motion planning collision detection and geometric complexity and future directions Features include Review of state of the art techniques and coverage of the main issues to be considered in the development of motion planners for use in real applications Focus on gross motion planning for articulated arms enabling robots to perform non contact tasks with relatively high tolerances plus brief consideration of mobile robots The use of efficient algorithms to tackle incremental

changes in the environment Illlustration of robot motion planning applications in virtual prototyping and the shipbuilding industry Demonstration of efficient path planners combining both local and global planning approaches in conjunction with efficient techniques for collision detection and distance computations International contributions from academia and industry Combining theory and practice this timely book will appeal to academic researchers and practising engineers in the fields of robotic systems mechatronics and computer science *Motion Planning for Wheeled Nonholonomic Systems* Linda Grace Bushnell,1994

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