Assignments for Meeting on Feb. 2, 2021 (1/2)


▶ Read Sections 3.3.3 and 5 in Karaman, S., & E. Frazzoli, ”Sampling-based algorithms for optimal motion planning”, The International Journal of Robotics Research, 30(7), 846–894, 2011. DOI: https://doi.org/10.1177/0278364911406761

▶ Scan the paper S. Karaman, & E. Frazzoli, ”Optimal kinodynamic motion planning using incremental sampling-based methods”, 49th IEEE Conference on Decision and Control (CDC), Atlanta, GA, 7681–7687, 2010. DOI: https://doi.org/10.1109/CDC.2010.5717430

Assignments for Meeting on Feb. 2, 2021 (2/2)

▶ Do the parts of Hand-in Exercise 2 from TSFS12 that concern RRT (Sections 4.1–4.2) and RRT* (Section A). Those that have taken TSFS12 should implement and evaluate an RRT* for the Dubins’ vehicle that is optimal with respect to path length, and then compare it with the results from the TSFS12 implementations.

▶ Next meeting: Tuesday February 2, 2021, at 15:15 in Zoom.

▶ Lecture responsibility: Anja Hellander.