

L7-1: Sampled-based Motion Planning

Hao Su

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| H | Show this help |
| Left & Right | Previous & Next step |
| P | Presenter console |
| F5 / ESC | Fullscreen: Enter / Exit |

Agenda

- Problem Formulation
- Probabilistic Roadmap Method (PRM)
- Rapidly-exploring Random Trees (RRT)

click to jump to the section.

Problem formulation