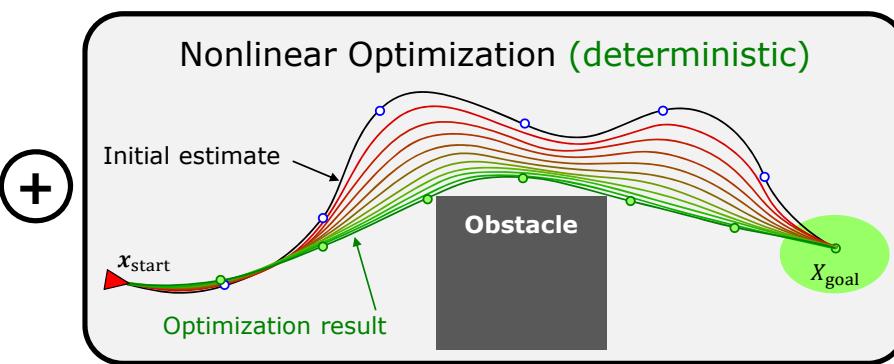
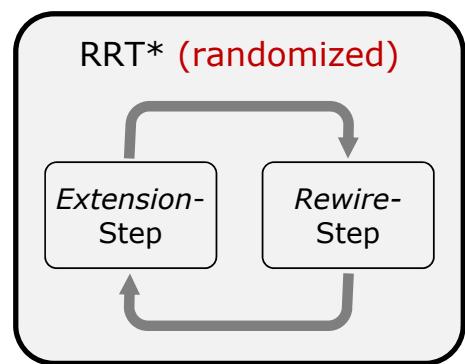
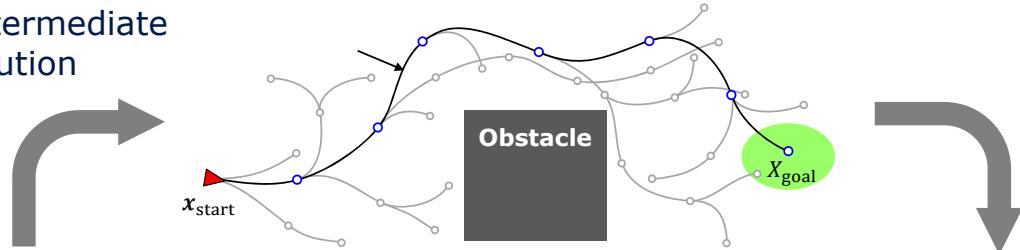


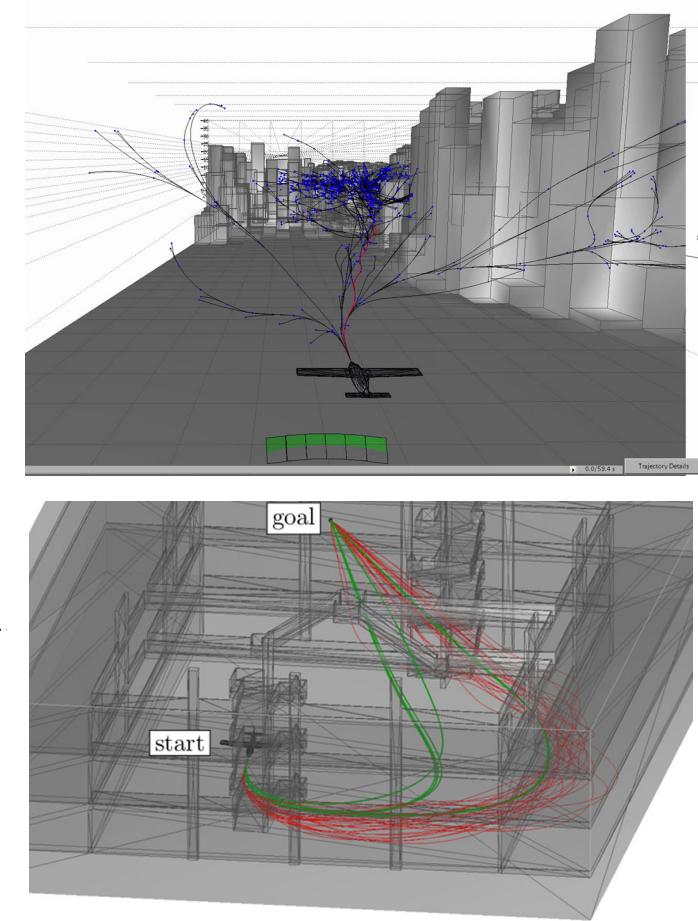
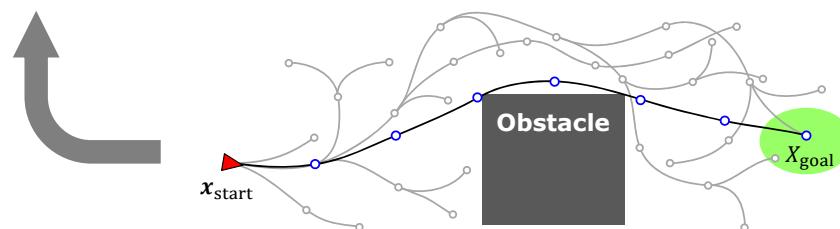
Hybrid Planning and Optimization Concept

Fakultät Elektrotechnik und Informationstechnik · Lehrstuhl Automatisierungstechnik · Prof. K. Janschek

RRT*-Intermediate Solution



Back-integration in
RRT* Search Tree



Ref.: Martin Seeman, A Partially Randomized Approach to Trajectory Planning and Optimization for Mobile Robots with Flat Dynamics, Dissertation TU Dresden, 2018.