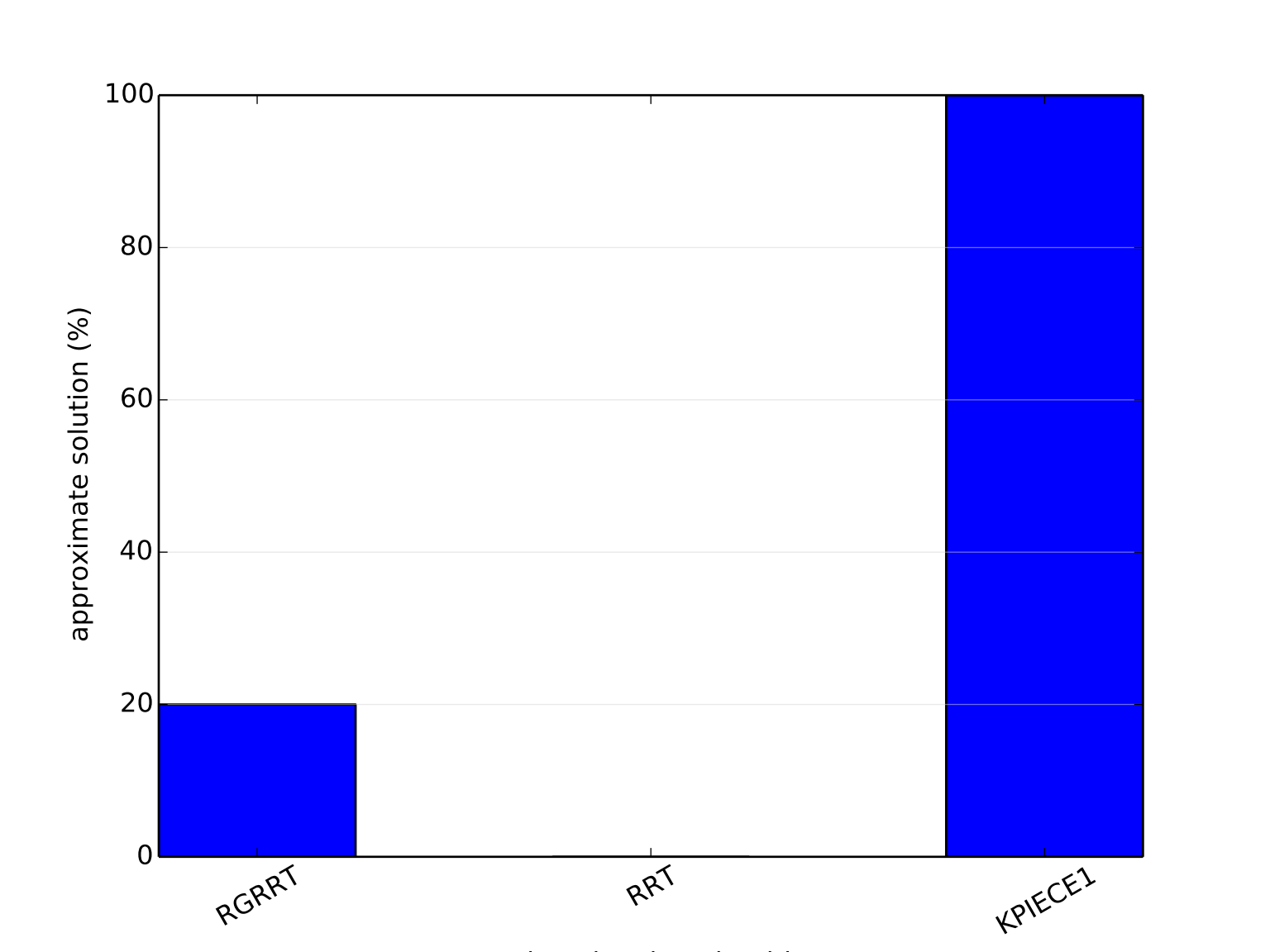
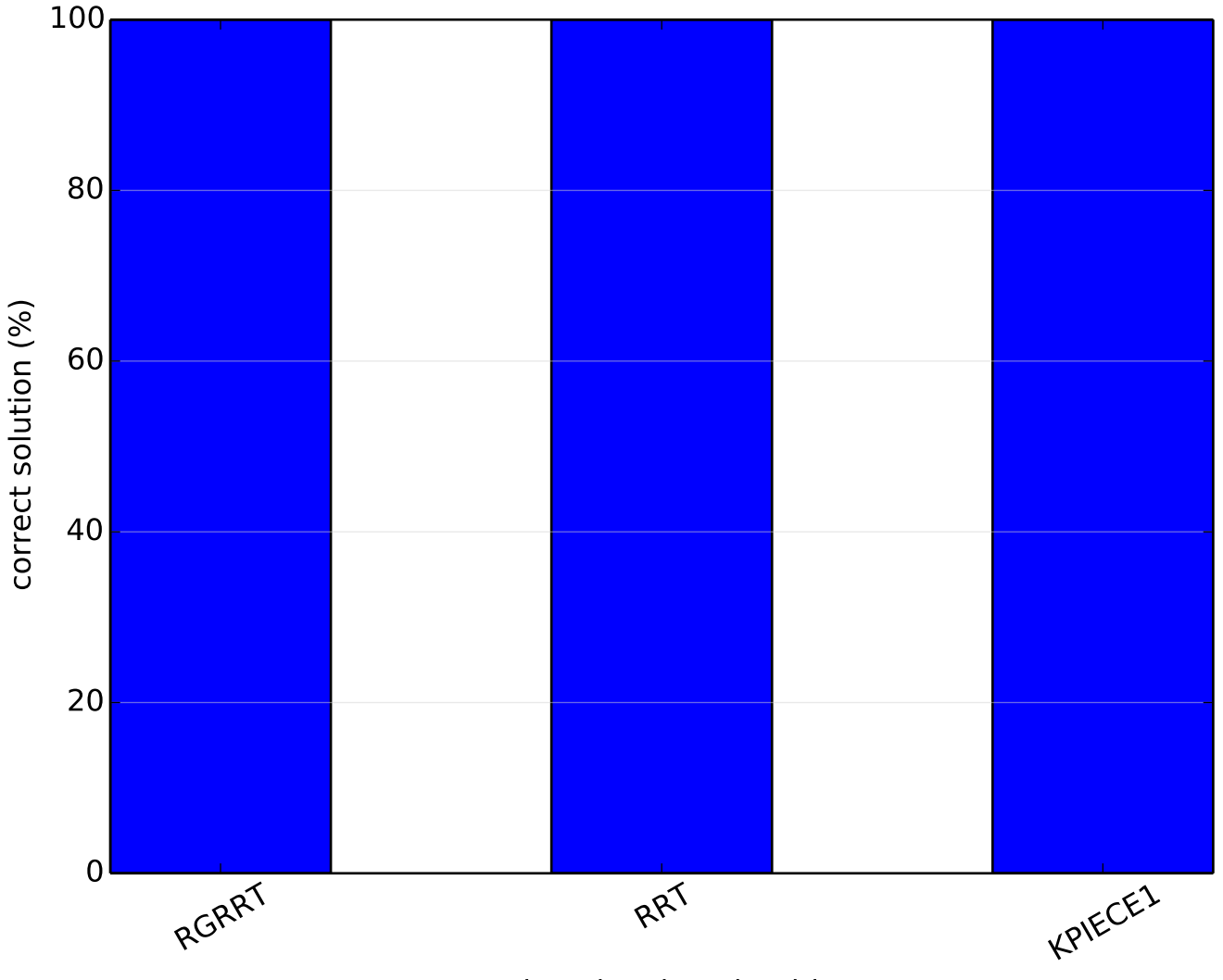
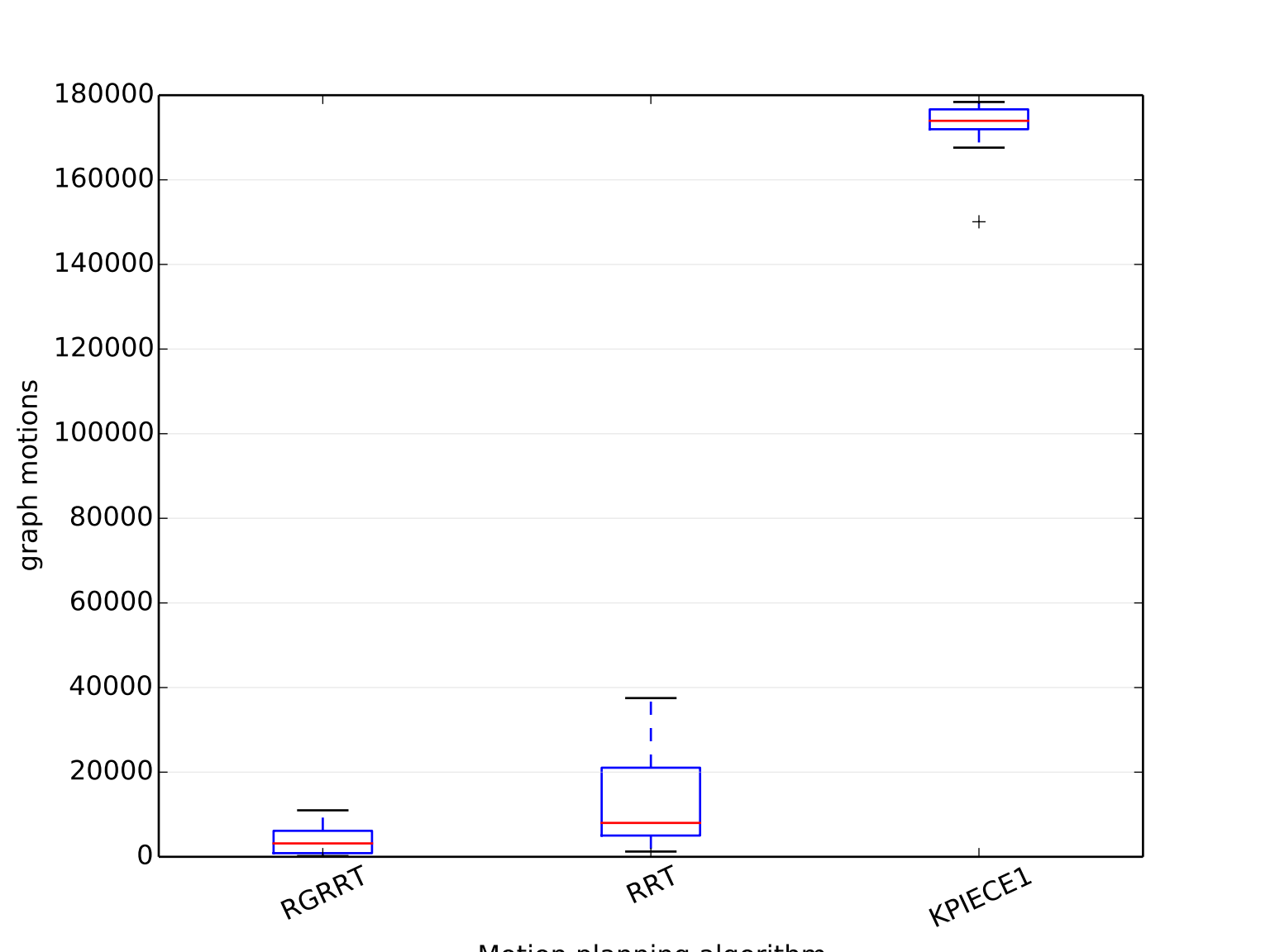
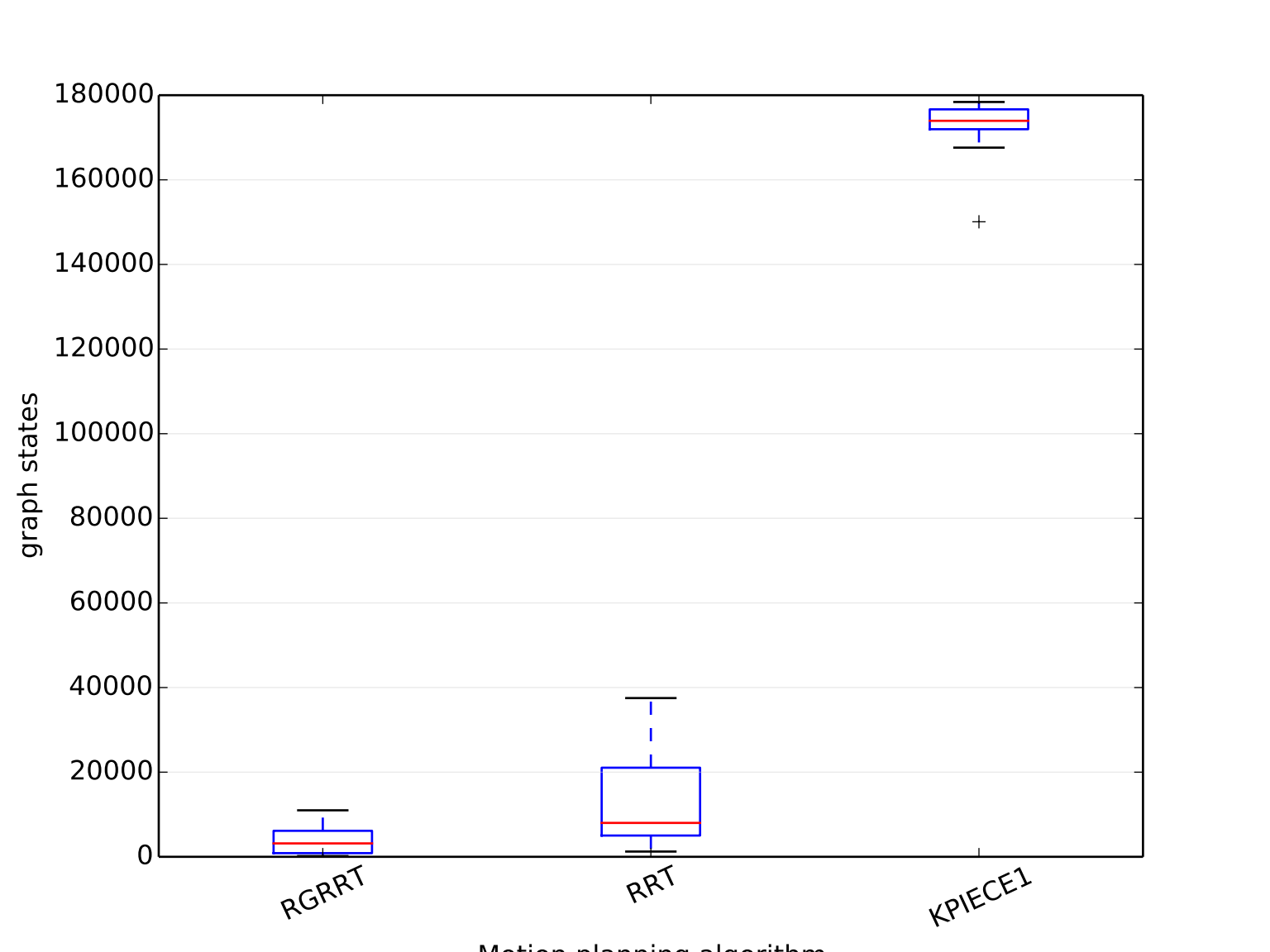
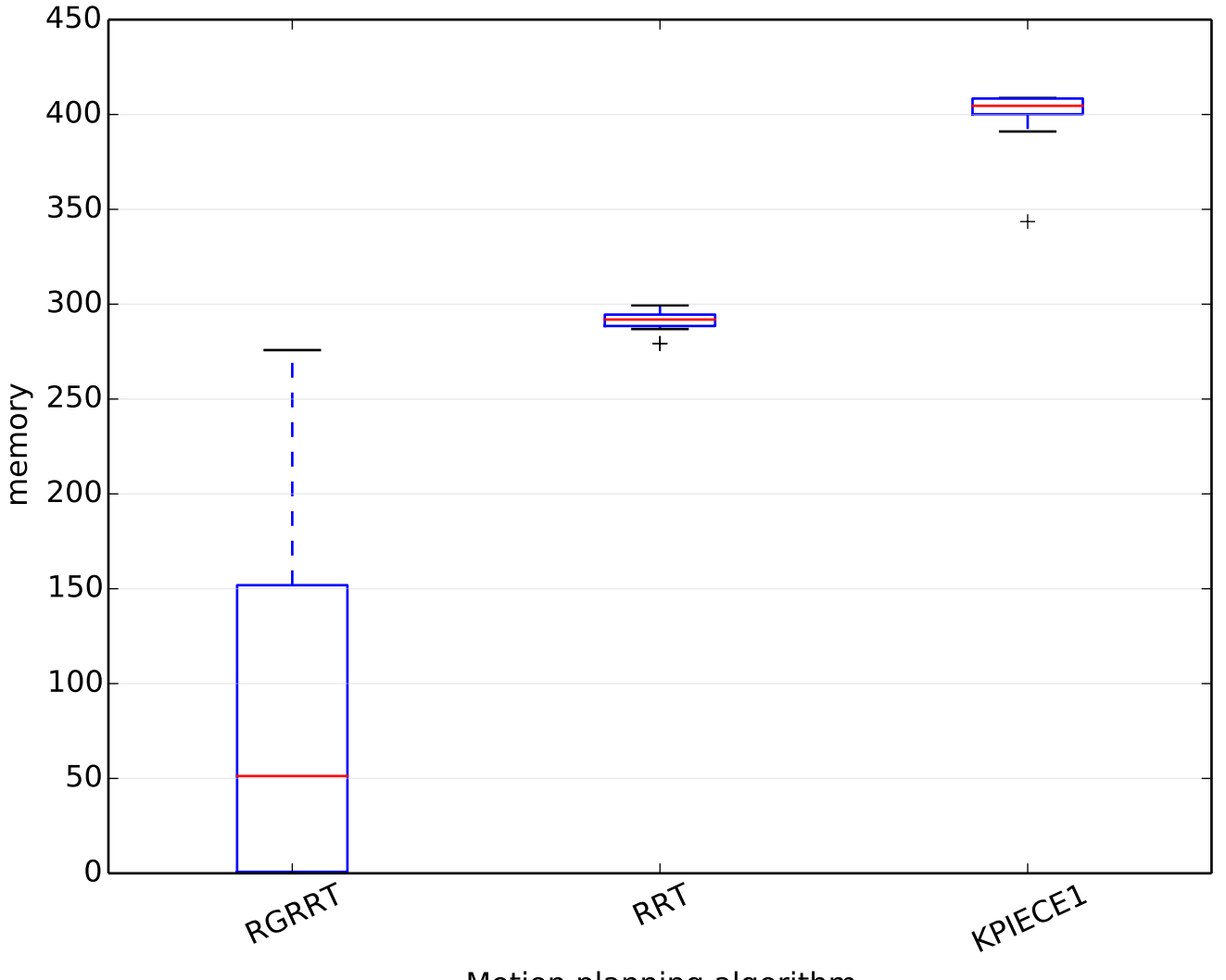
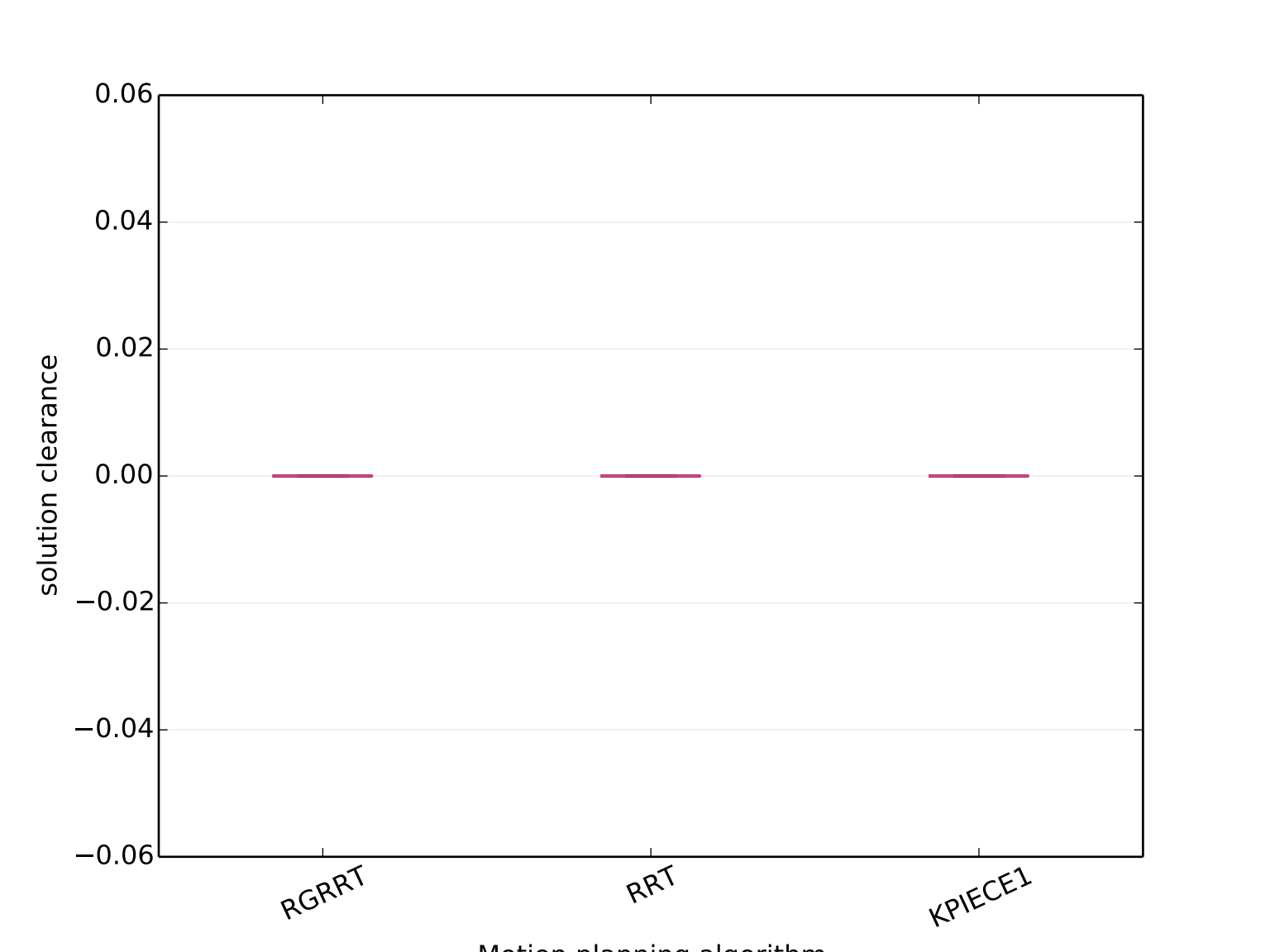

100
80
60
40
20
0
approximate solution (%)
RGRRT
RRT
KPIECE1

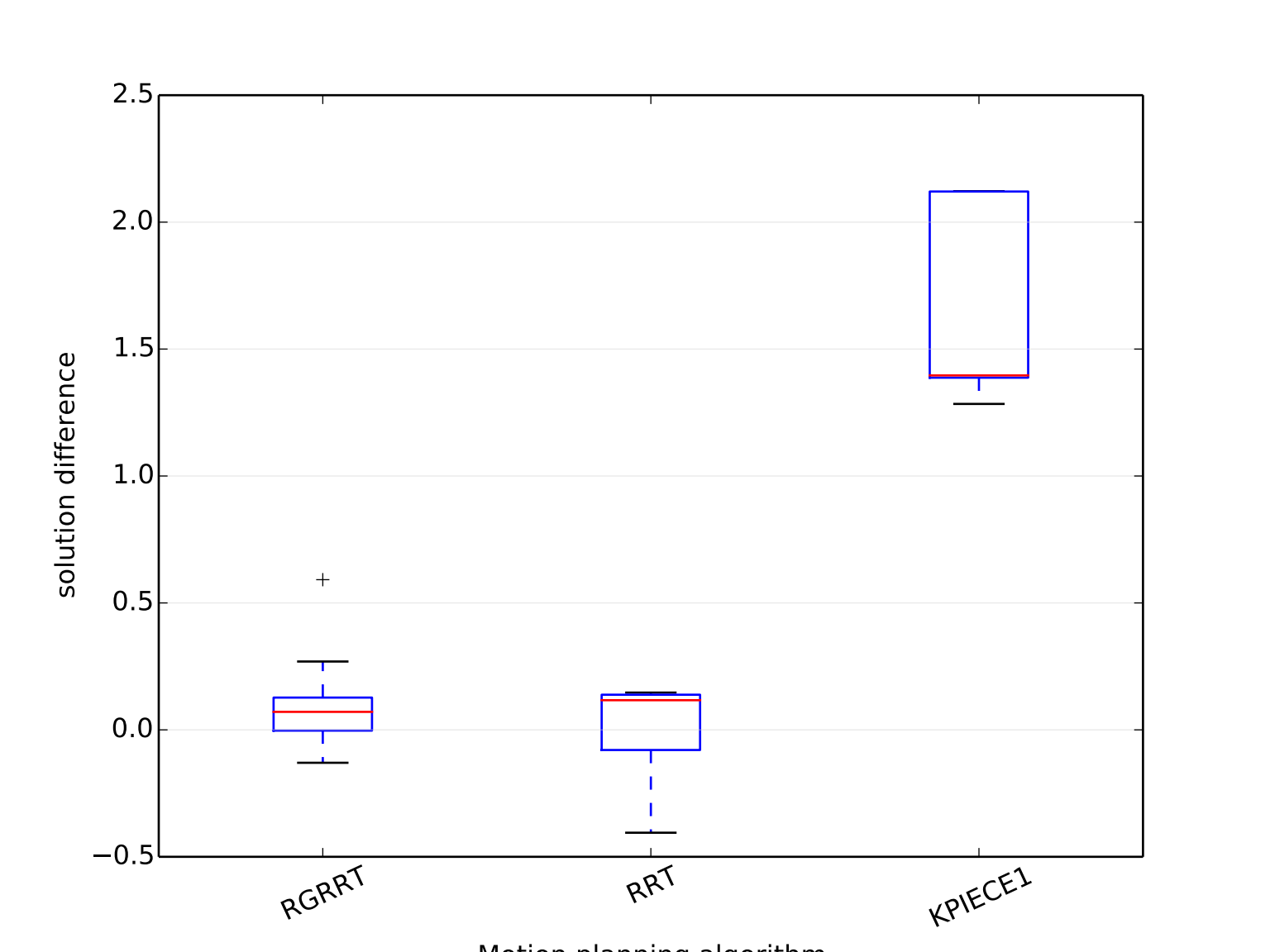

100
80
60
40
20
0
correct solution (%)
RGRRT
RRT
KPIECE1

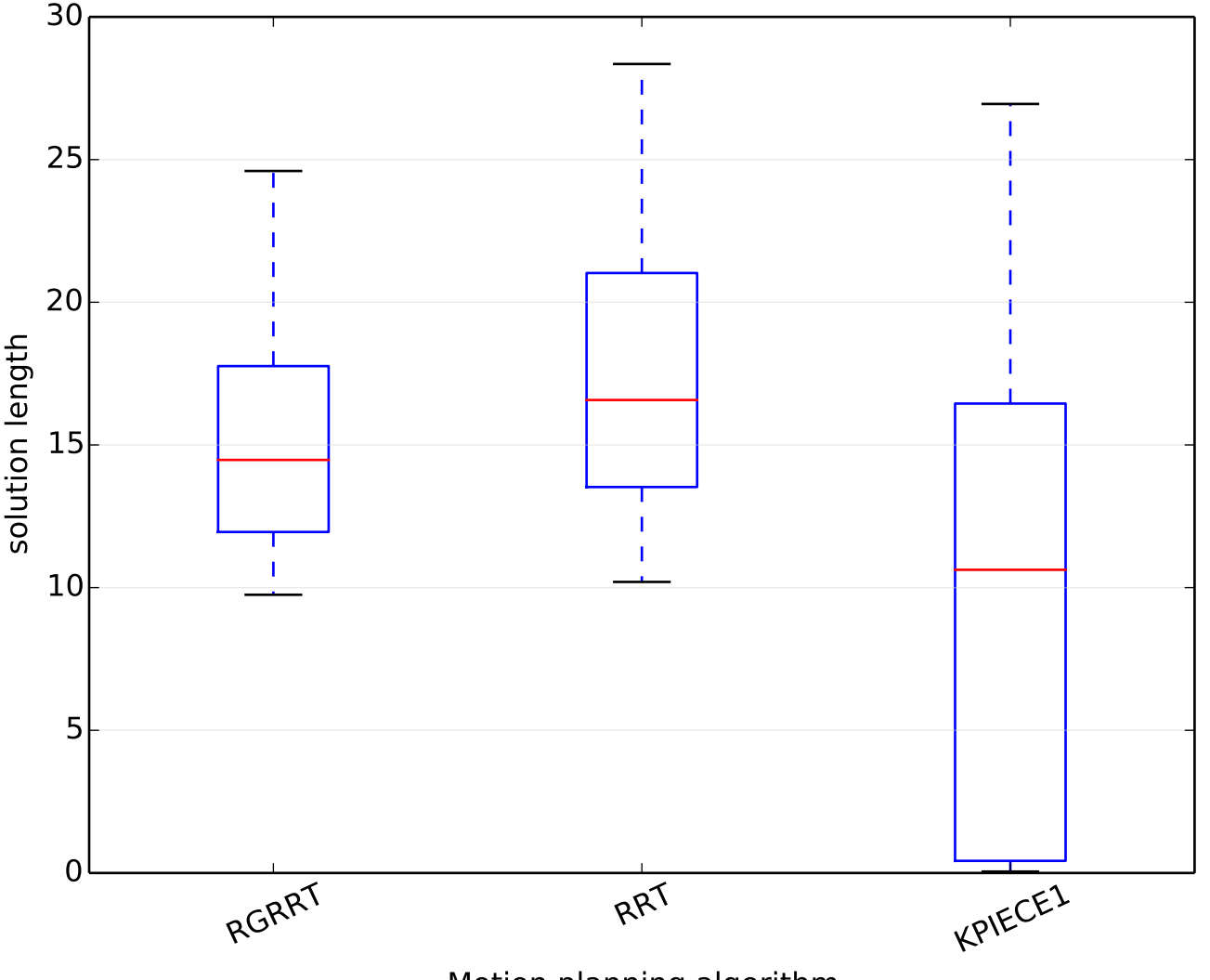

180000
160000
140000
120000
100000
80000
60000
40000
20000
0
graph motions
RGRRT
RRT
KPIECE1
Motion planning algorithm

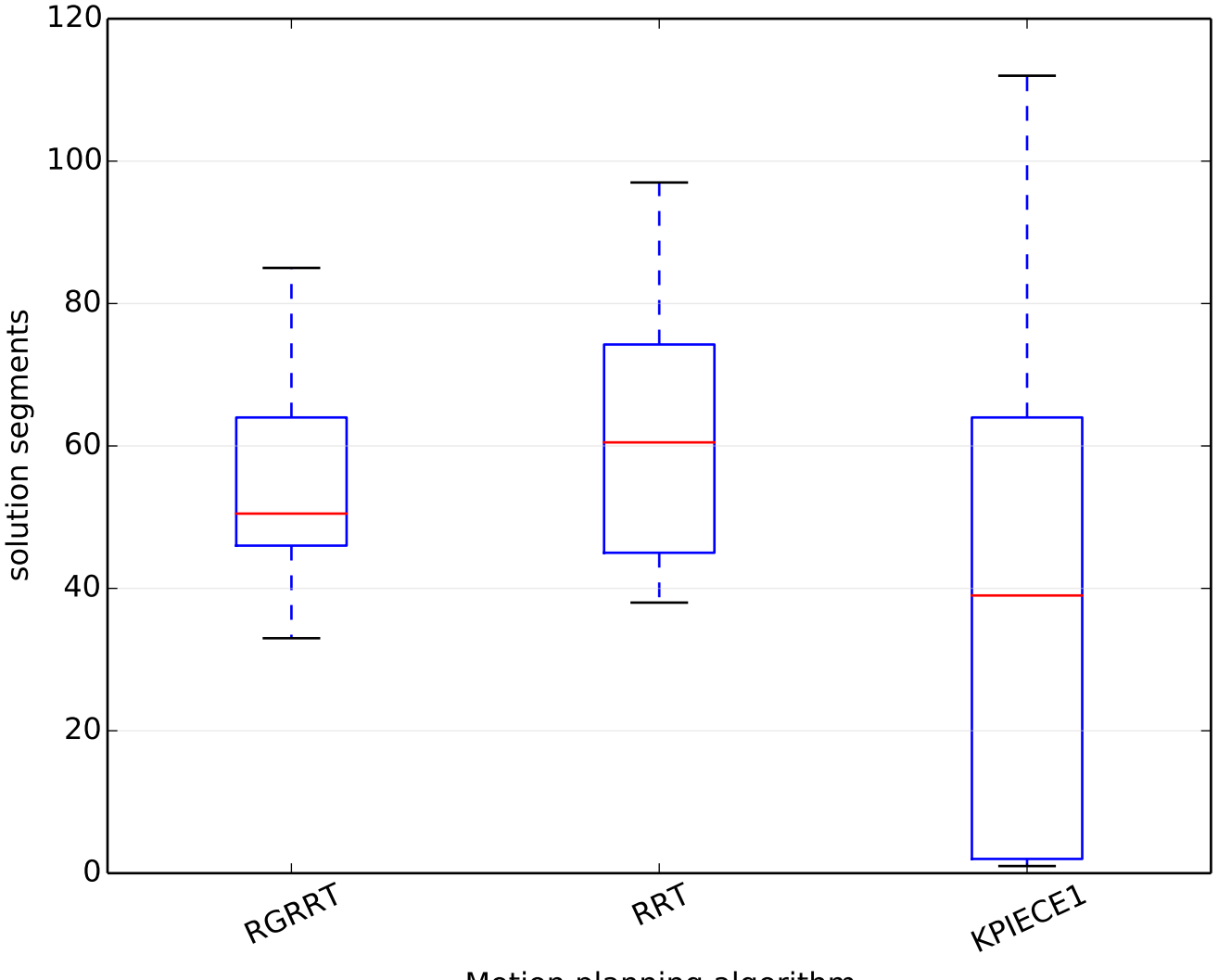

180000
160000
140000
120000
100000
80000
60000
40000
20000
0
graph states
RGRRT
RRT
KPIECE1
Motion planning algorithm

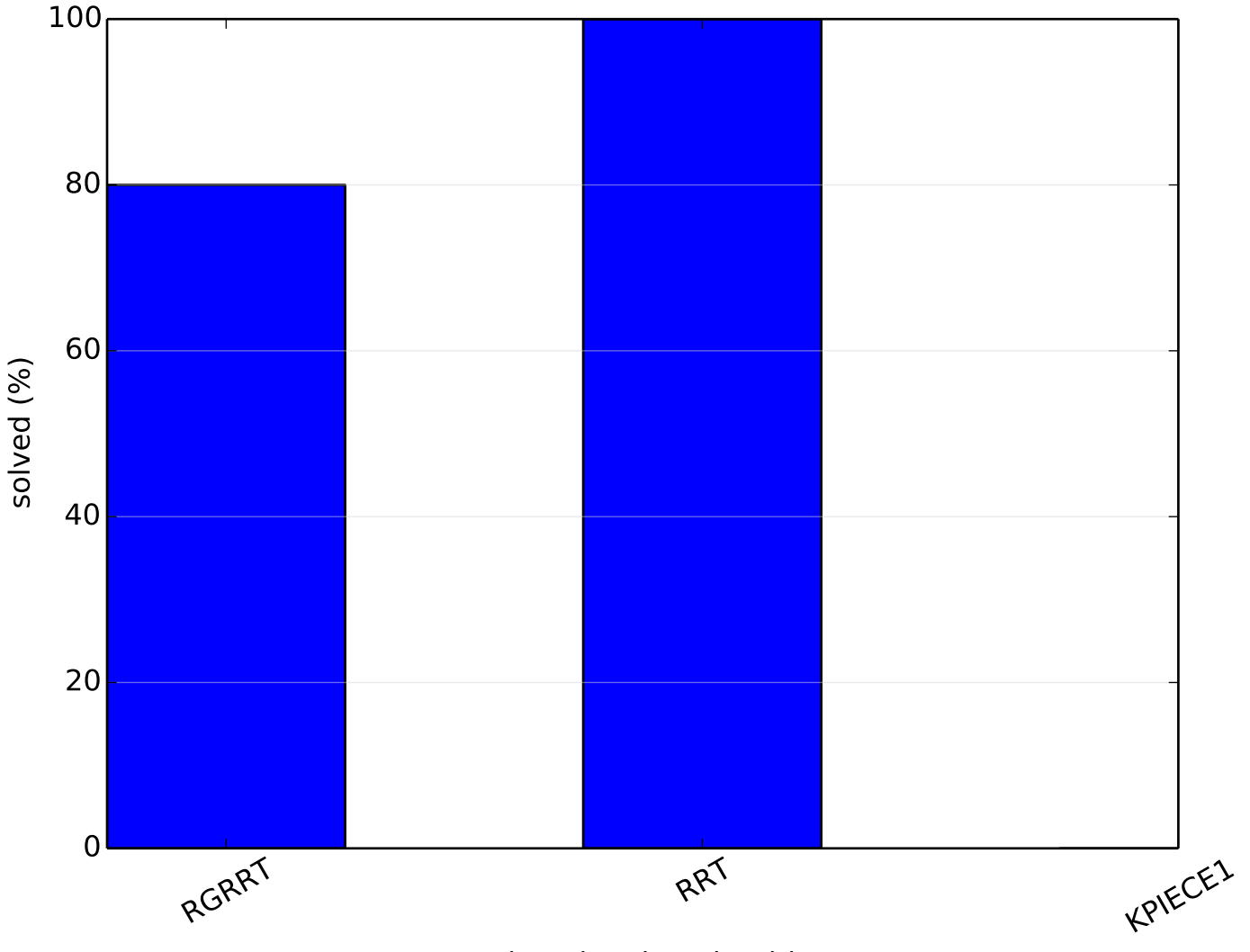

450
400
350
300
250
200
150
100
50
0
memory
RGRRT
RRT
KPIECE1
Motion planning algorithm

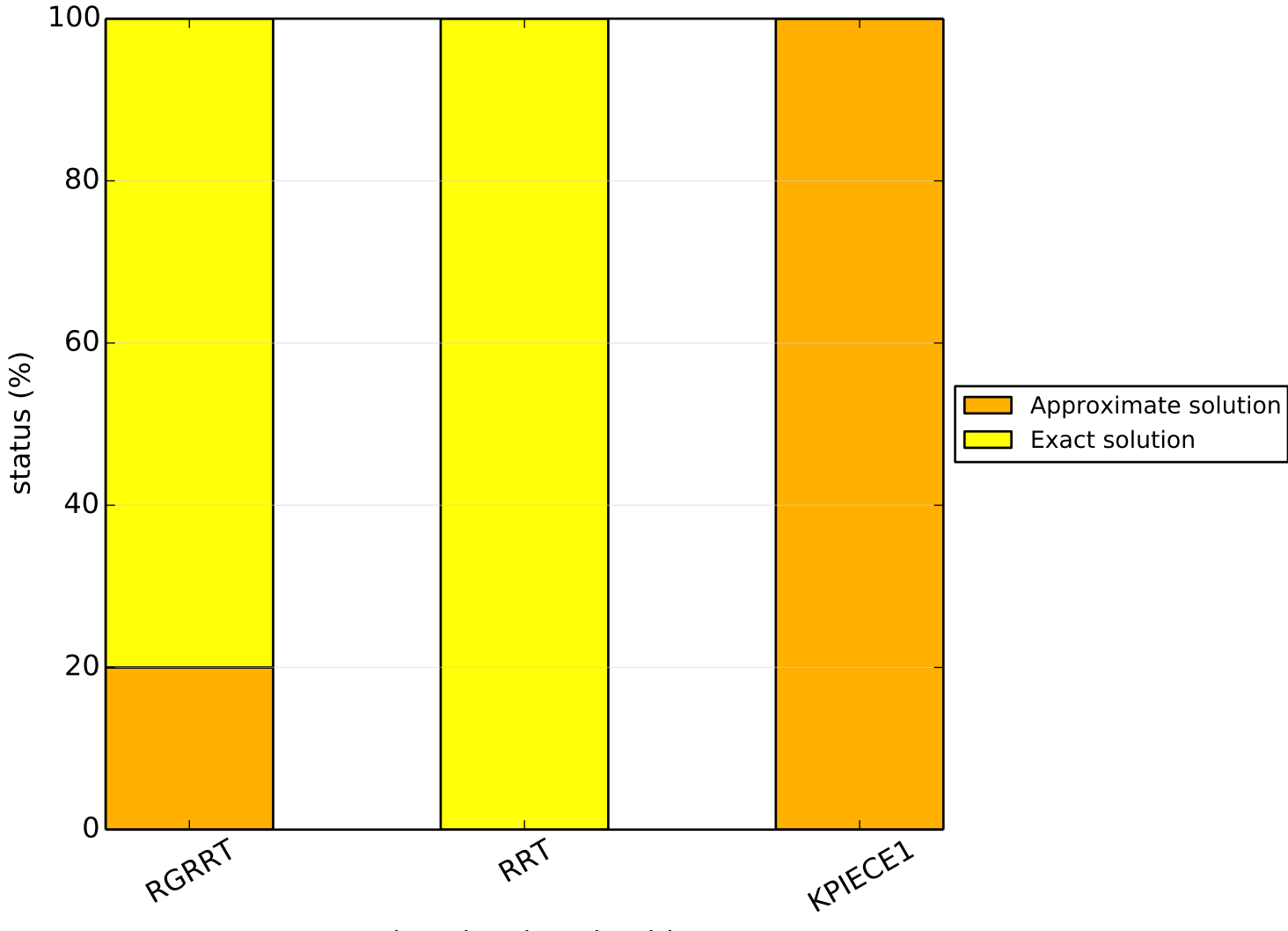

0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
solution clearance
RGRRT
RRT
KPIECE1
Motion planning algorithm

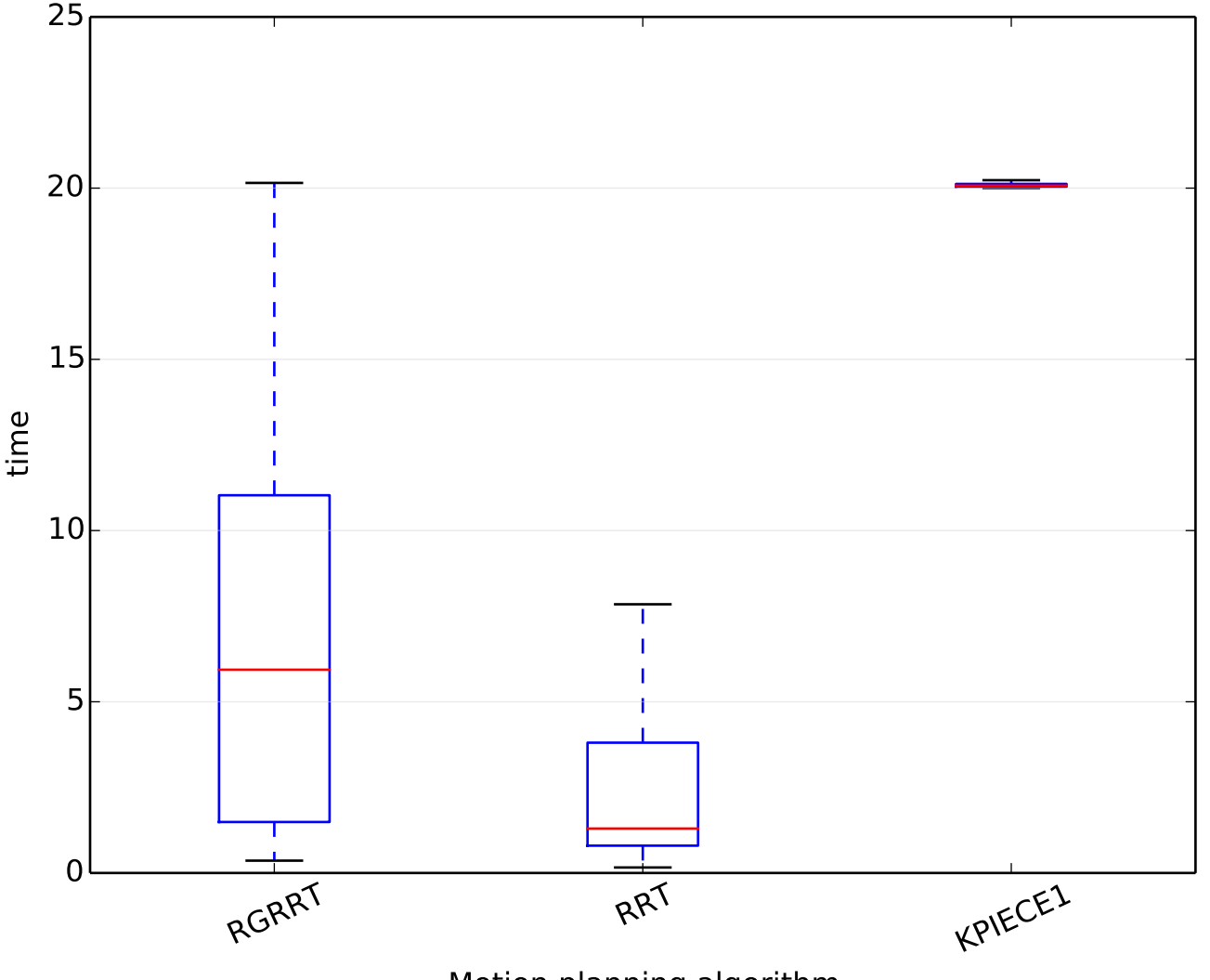

2.5
2.0
1.5
1.0
0.5
0.0
−0.5
solution difference
RGRRT
RRT
KPIECE1
Motion planning algorithm

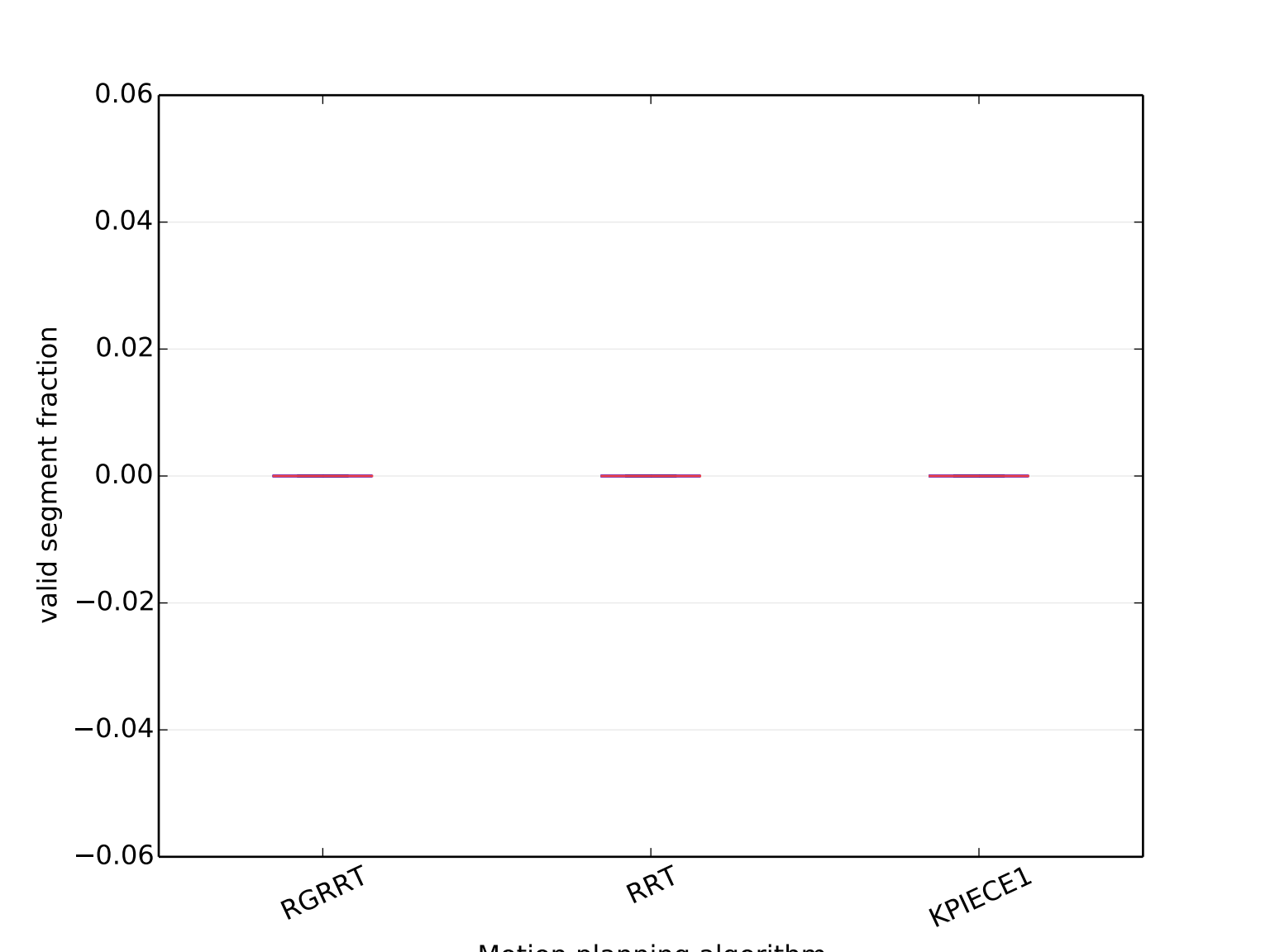

30
25
20
15
10
5
0
solution length
RGRRT
RRT
KPIECE1
Motion planning algorithm


120
100
80
60
40
20
0
solution segments
RGRRT
RRT
KPIECE1
Motion planning algorithm


100
80
60
40
20
0
solved (%)
RGRRT
RRT
KPIECE1


100
80
60
40
20
0
status (%)
RGRRT
RRT
KPIECE1
Approximate solution
Exact solution


25
20
15
10
5
0
time
RGRRT
RRT
KPIECE1
Motion planning algorithm


0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
valid segment fraction
RGRRT
RRT
KPIECE1
Motion planning algorithm

Experiment "Benchmark-KinodynamicCar"

Number of averaged runs: 20

Time limit per run: 20 seconds

Memory limit per run: 1000 MB