**Characteristics**

* RRT is heavily attracted by unexplored portions of the space.
* RRT Quickly expands in few directions to quickly explore the four corners of the square.
* Balance between greedy search and exploration.
* Simple and easy to implement.
* The path from RRT could be a Zig-Zag.

Steven M. La Valle, “Rapidly-Exploring Random Trees: A new tool for path planning”

**Behavior**

* Diagram.

**Improvements**

* RRT\* works similar to RRT.
* RRT\* tries to smoothen the tree branches. Zig-Zag will disappear.
* Nodes number reaching Infinity, returned path will be shorter.
* RRT\* is more organized than RRT.

Iram Noreen1, Amna Khan2, Zulfiqar Habib3, “A Comparison of RRT, RRT\* and RRT\*-Smart Path Planning Algorithms”

**Big Problem**

* If no Path found, it won’t stop.

¡Agregar Vídeo No\_Solution!

**Map 11 Experiment**

Agregar RRT Mapa 11.

**A\* vs RRT**

* A\* finds solution faster than RRT.
* RRT is busy exploring the space.
* RRT Performs better on open space.
* A\* Usually ends up with a shorter path with fewer edges.
* RRT won’t show the same path everytime. A\* is exact everytime.