

ENPM661 - Quiz 3

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1

They are probabilistically complete, i.e the probability of finding a solution if one exists approaches 1 as runtime approaches ∞

2

They are asymptotically optimal, i.e the solution approaches the optimal solution as runtime approaches ∞

3

When the environment is likely to change from one moment to the next, e.g mobile robots, robots in dynamic environments.

4

When the robot is fixed in place, the workspace is well defined and unlikely to change.

5

RRT, RRT*, RRT#. PRM is not well suited for problems where we cannot solve the two-point boundary value problem.