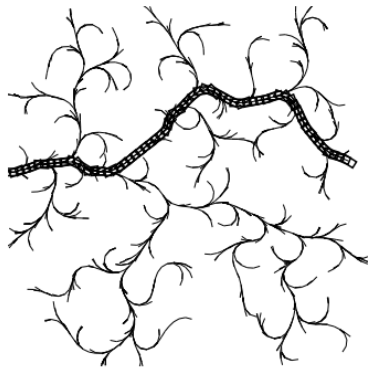
Rapidly-Exploring Random Trees (RRT)

Rapidly-Exploring Random Trees: A New Tool for Path Planning

Steven M. LaValle
Department of Computer Science
Iowa State University
Ames, IA 50011 USA
lavalle@cs.iastate.edu

Abstract

We introduce the concept of a Rapidly-exploring Random Tree (RRT) as a randomized data structure that is designed for a broad class of path planning problems. While they share many of the beneficial properties of existing randomized planning techniques, RRTs are specifically designed to handle nonholonomic constraints (including dynamics) and high degrees of freedom. An RRT is iteratively expanded by applying control inputs that drive the system slightly toward randomly-selected points, as opposed to requiring point-to-point convergence, as in the probabilistic roadmap approach. Several desirable properties and a basic implementation of RRTs are discussed. To date, we have successfully applied RRTs to holonomic, nonholonomic, and kinodynamic planning problems of up to twelve degrees of freedom.



1 Introduction

Over the past decade, several randomized approaches have been proposed and successfully applied to the gen-

(a) Technical Report 98-11 Oct. 1998

(b) S. M. LaValle

Figure: Currently Professor at University of Illinois and Chief Scientist of VR/AR/MR at Huawei.

RRT Construction Algorithm

```
GENERATE_RRT(x_init, K, Δt)
1   T.init(x_init);
2   for k = 1 to K do
3       x_rand ← RANDOM_STATE();
4       x_near ← NEAREST_NEIGHBOR(x_rand, T);
5       u ← SELECT_INPUT(x_rand, x_near);
6       x_new ← NEW_STATE(x_near, u, Δt);
7       T.add_vertex(x_new);
8       T.add_edge(x_near, x_new, u);
9   Return T
```

Figure: Source [LaValle, 1998]

Properties

- Relative simplicity;
- Bias toward unexplored space:
  - State selection related to Voronoi region size;
- Probabilistic completeness;
- Metric determines performance.

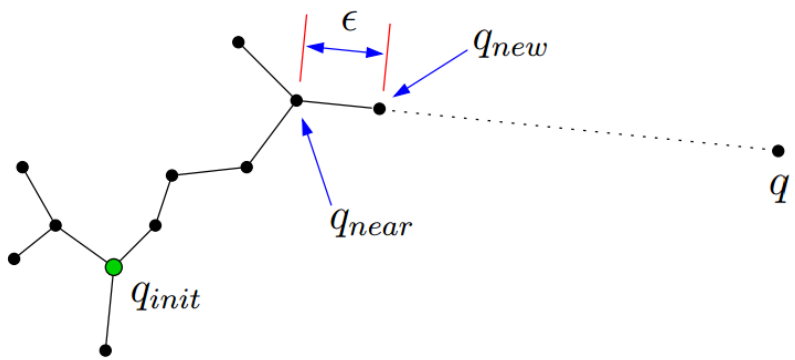


Figure: Source [Kuffner & LaValle, 2000]

Variants

- Obstacles:
  - Selection of random free states;
  - Transition validity for new states;
- Bias toward goal:
  - Avoid "bad luck";
  - Need to be slight;
- Movement constraints:
  - Nonholonomic;
  - Rigid-body;
- BiRRT, RRT*, Theta*-RRT, ...

References

S. M. Lavalle, *Rapidly-Exploring Random Trees: A New Tool for Path Planning*, 1998, [Online]. Available: http://msl.cs.uiuc.edu/~lavalle/papers/Lav98c.pdf

J. J. Kuffner and S. M. LaValle, "RRT-Connect: An Efficient Approach to Single-Query Path Planning," *Proceedings IEEE International Conference on Robotics and Automation*, pp 995–1001, 2000.