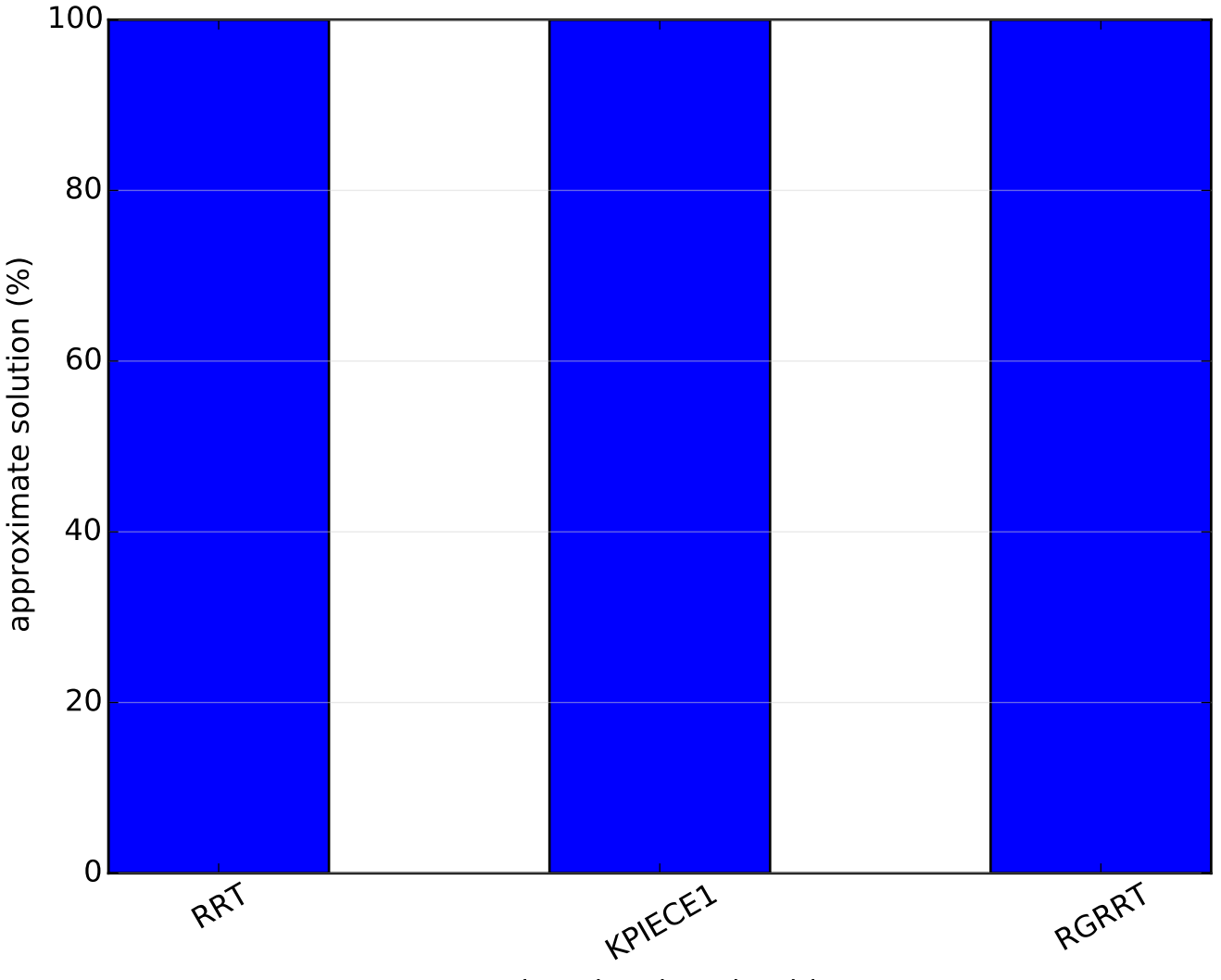
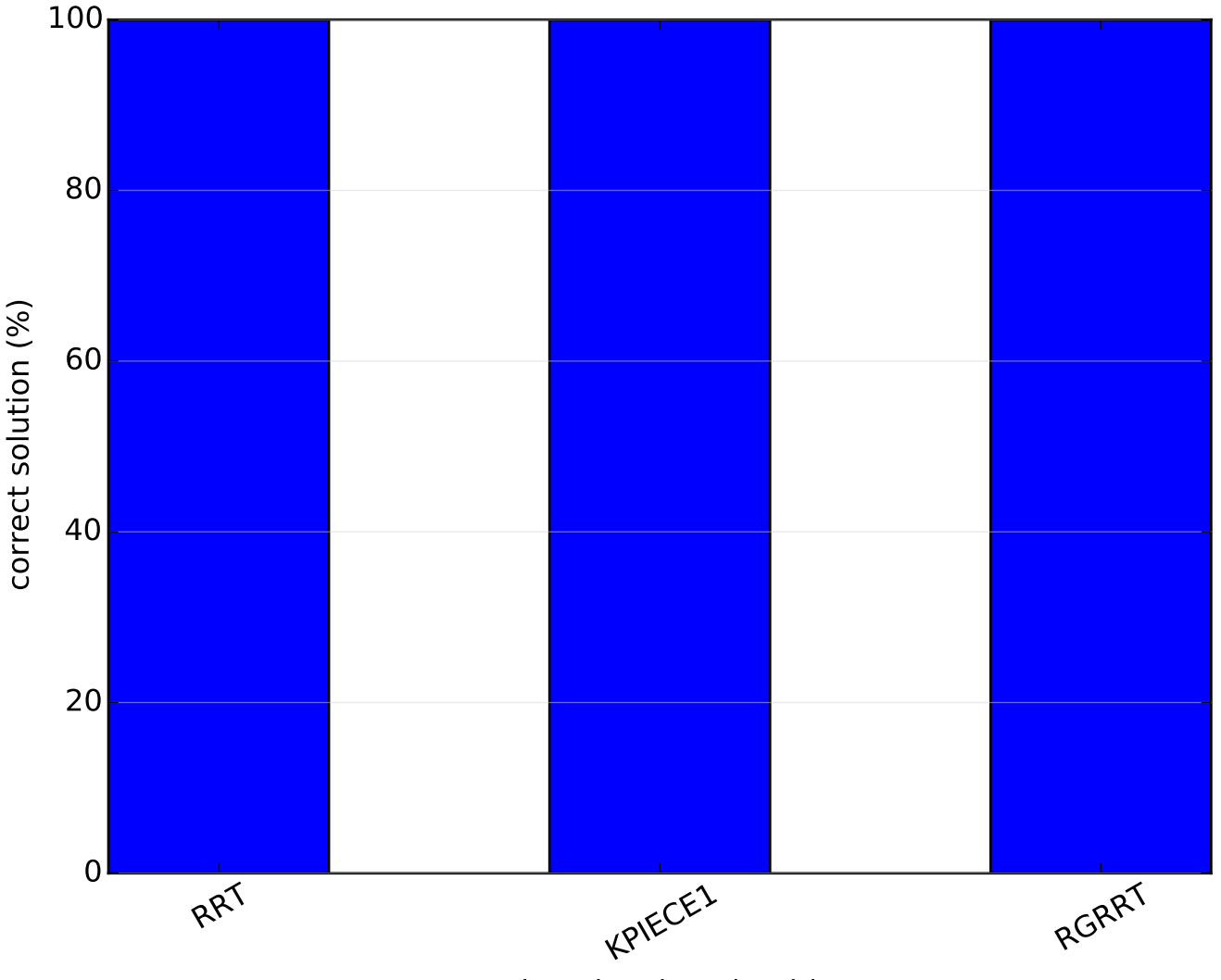
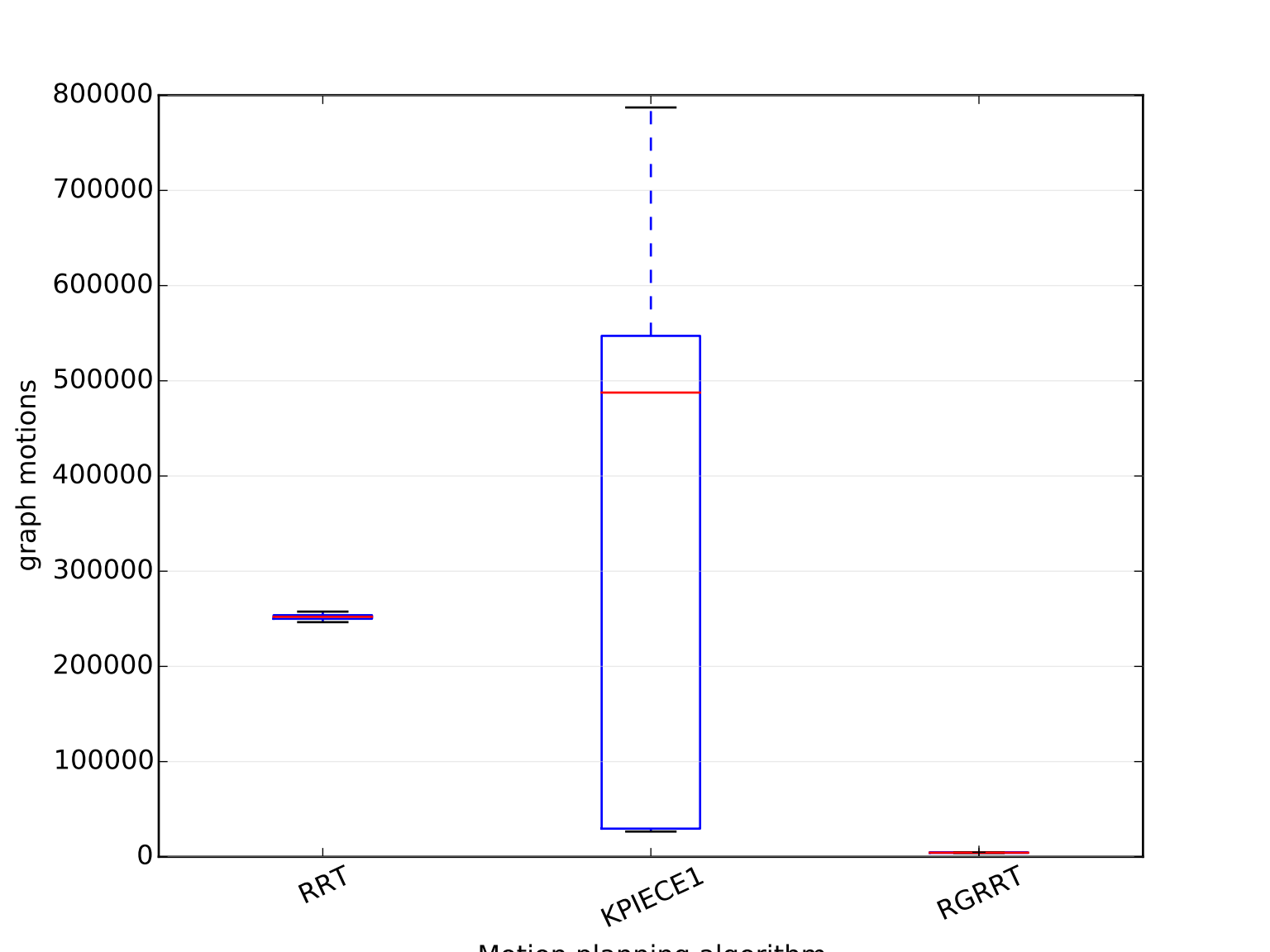
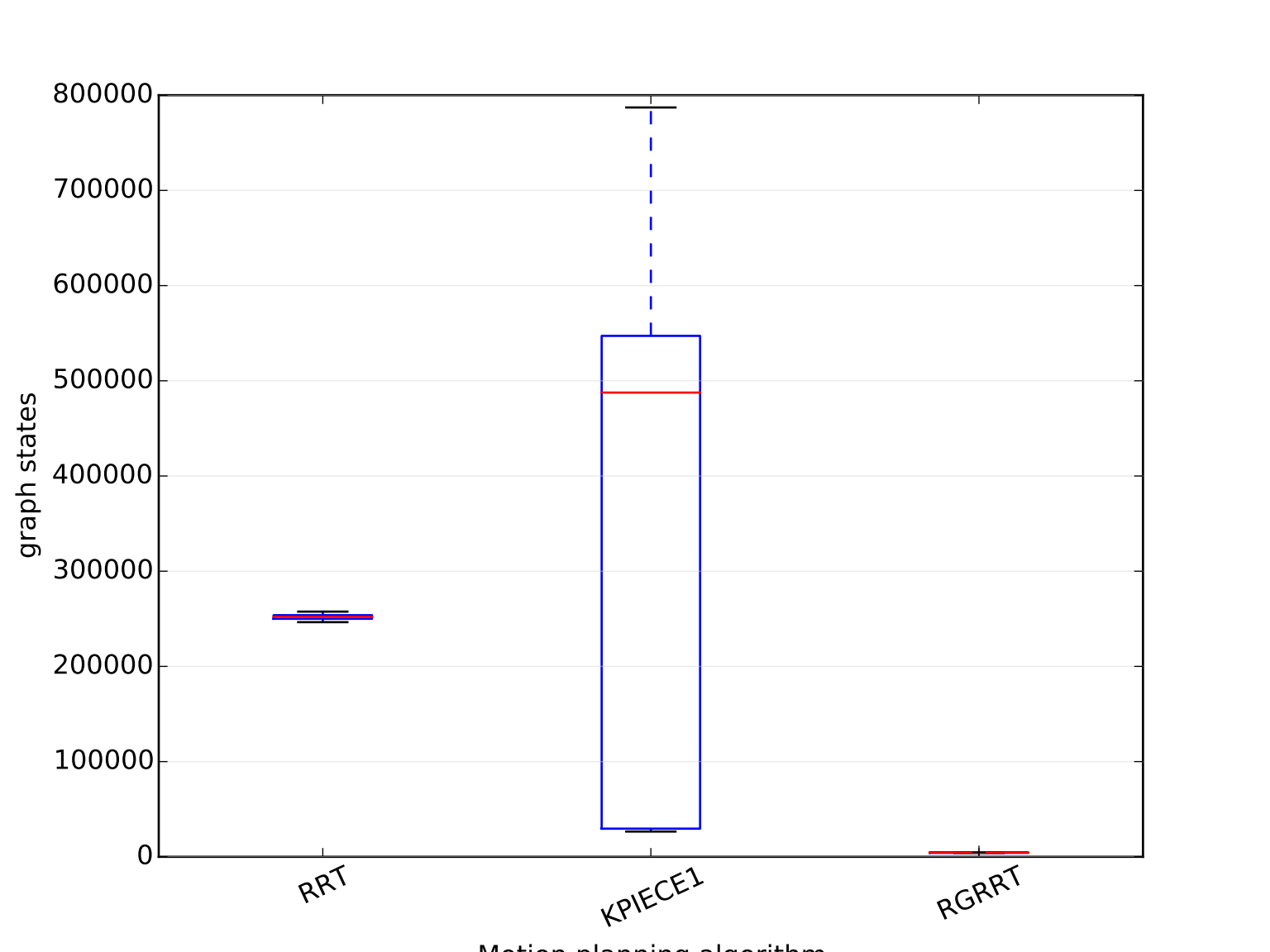
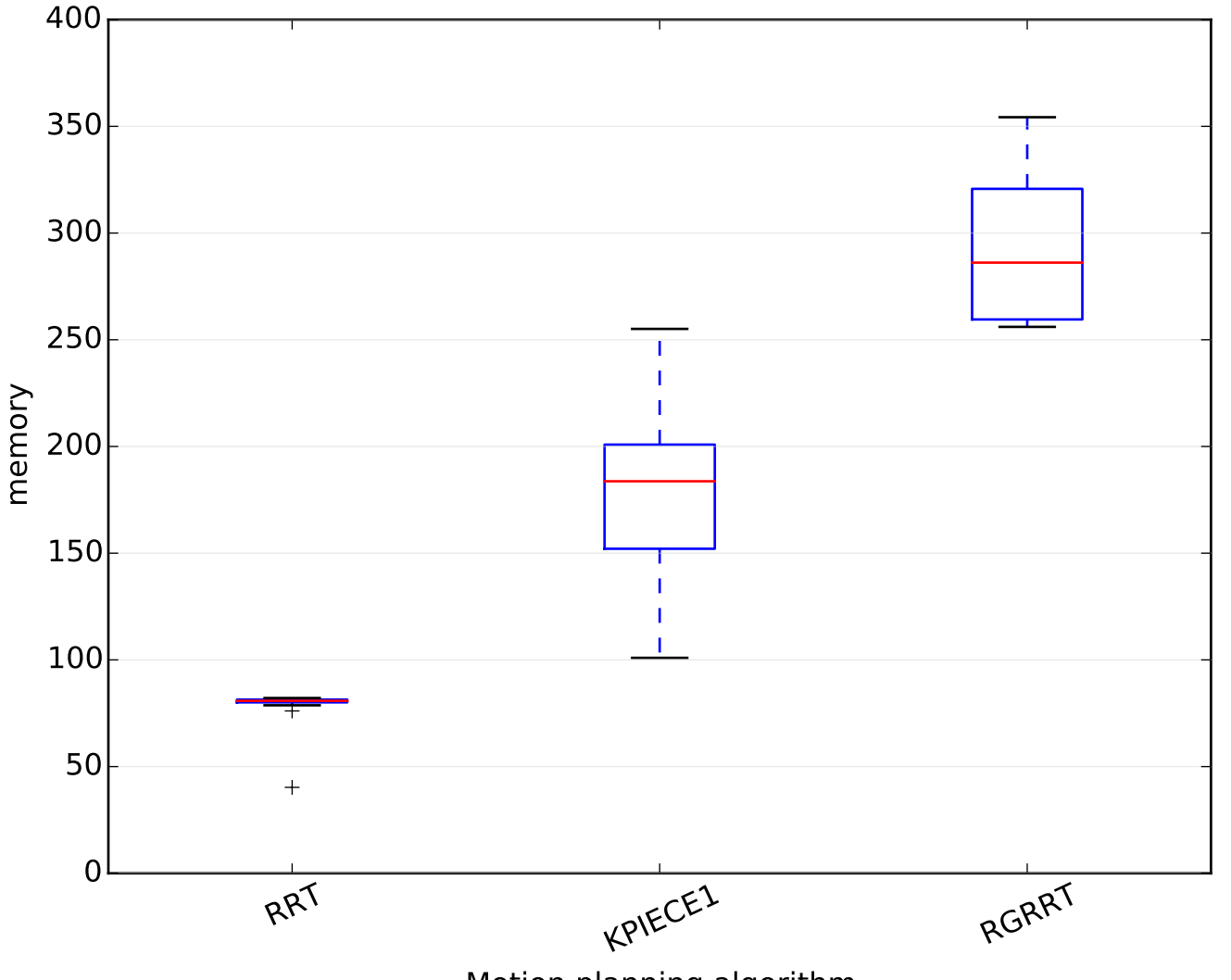
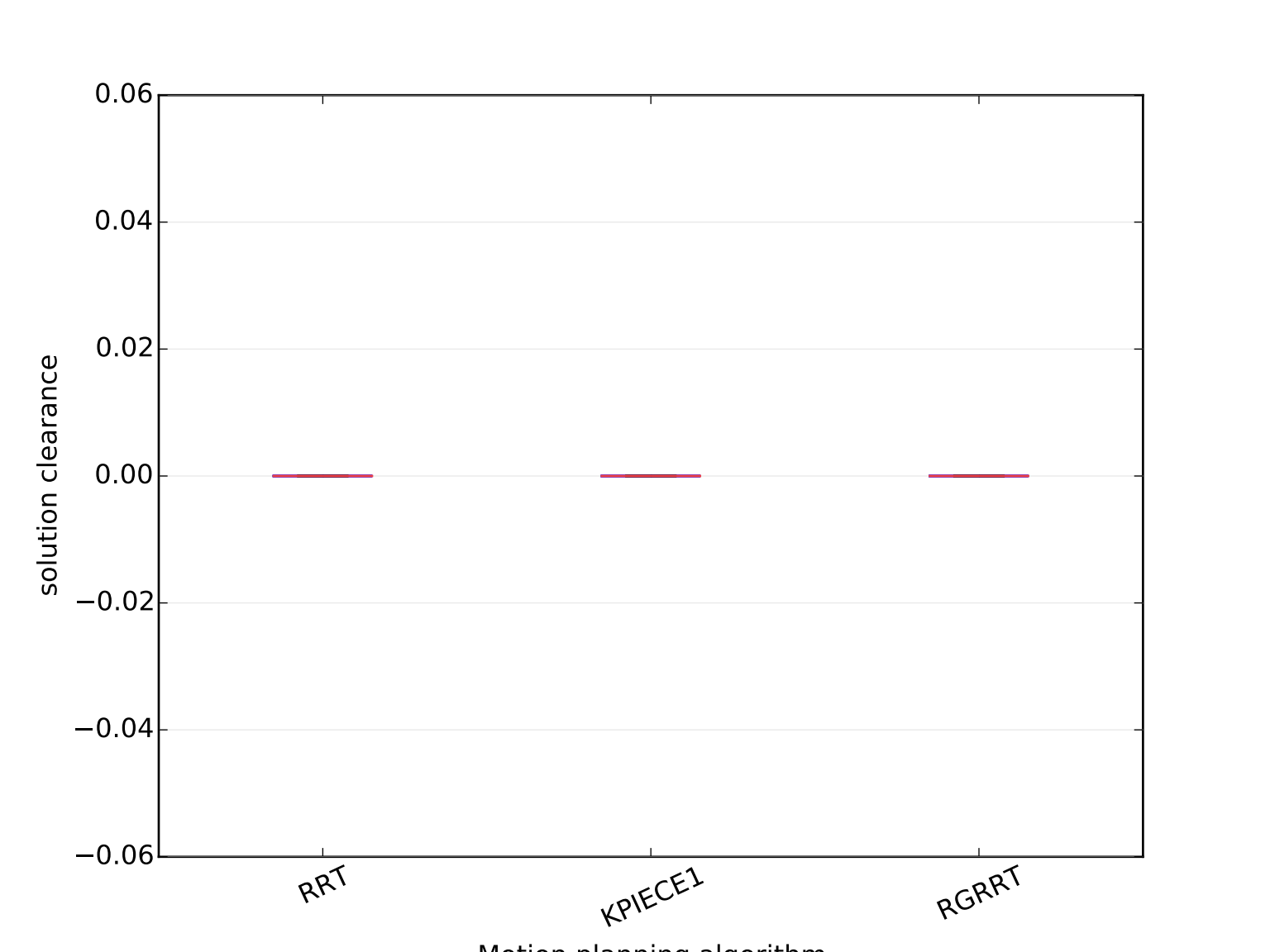

100
80
60
40
20
0
approximate solution (%)
RRT
KPIECE1
RGRRT

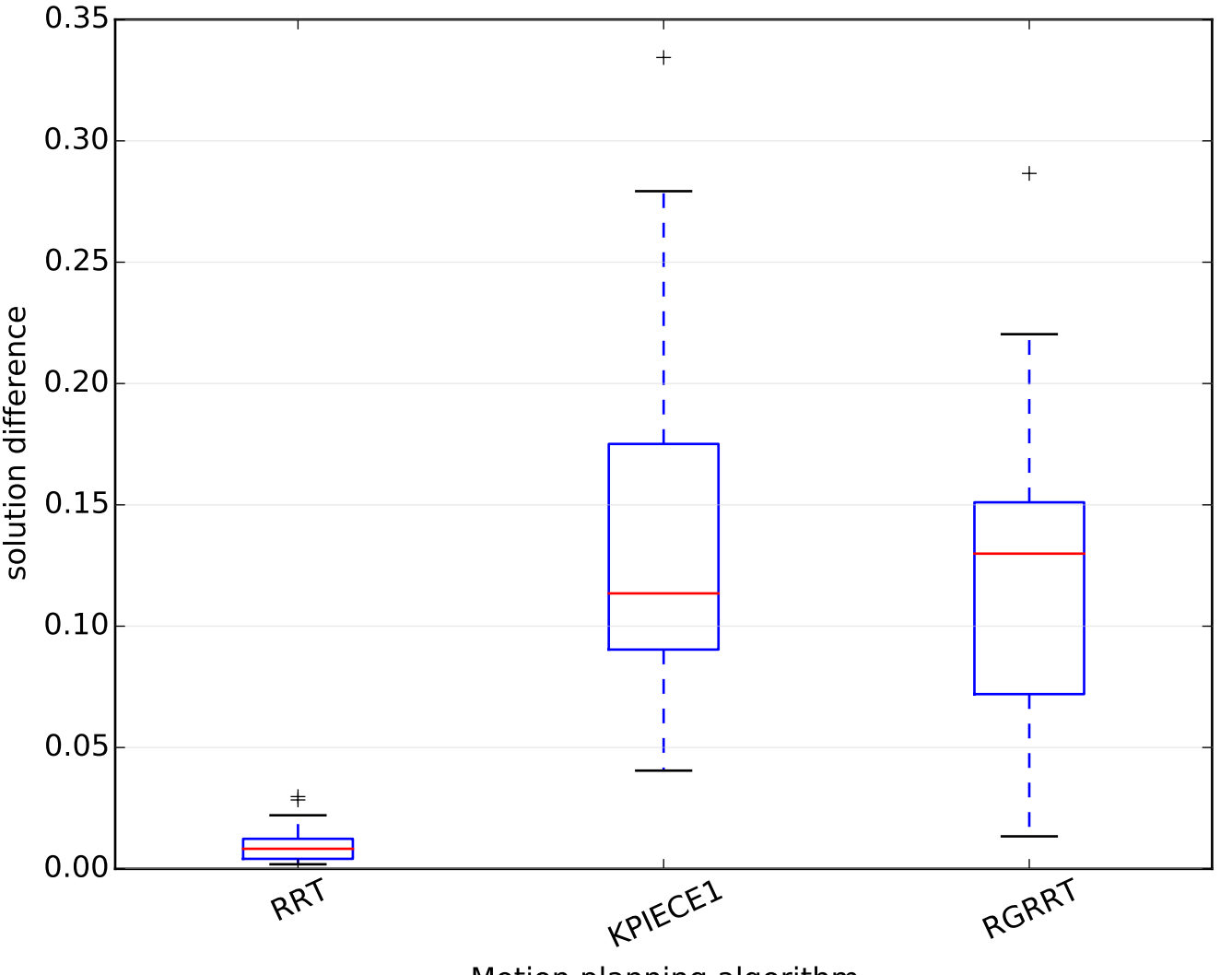

100
80
60
40
20
0
correct solution (%)
RRT
KPIECE1
RGRRT

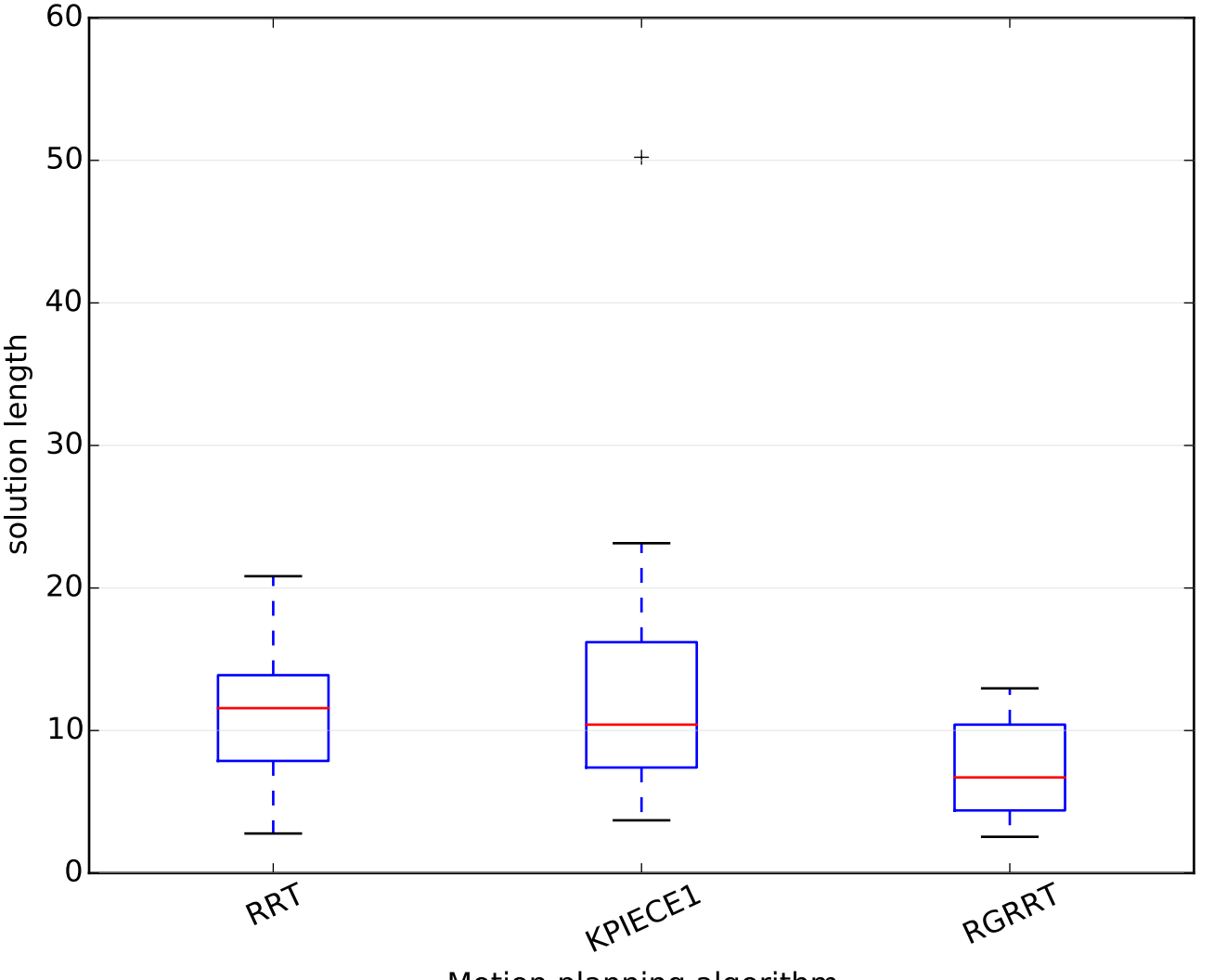

800000
700000
600000
500000
400000
300000
200000
100000
0
graph motions
RRT
KPIECE1
RGRRT

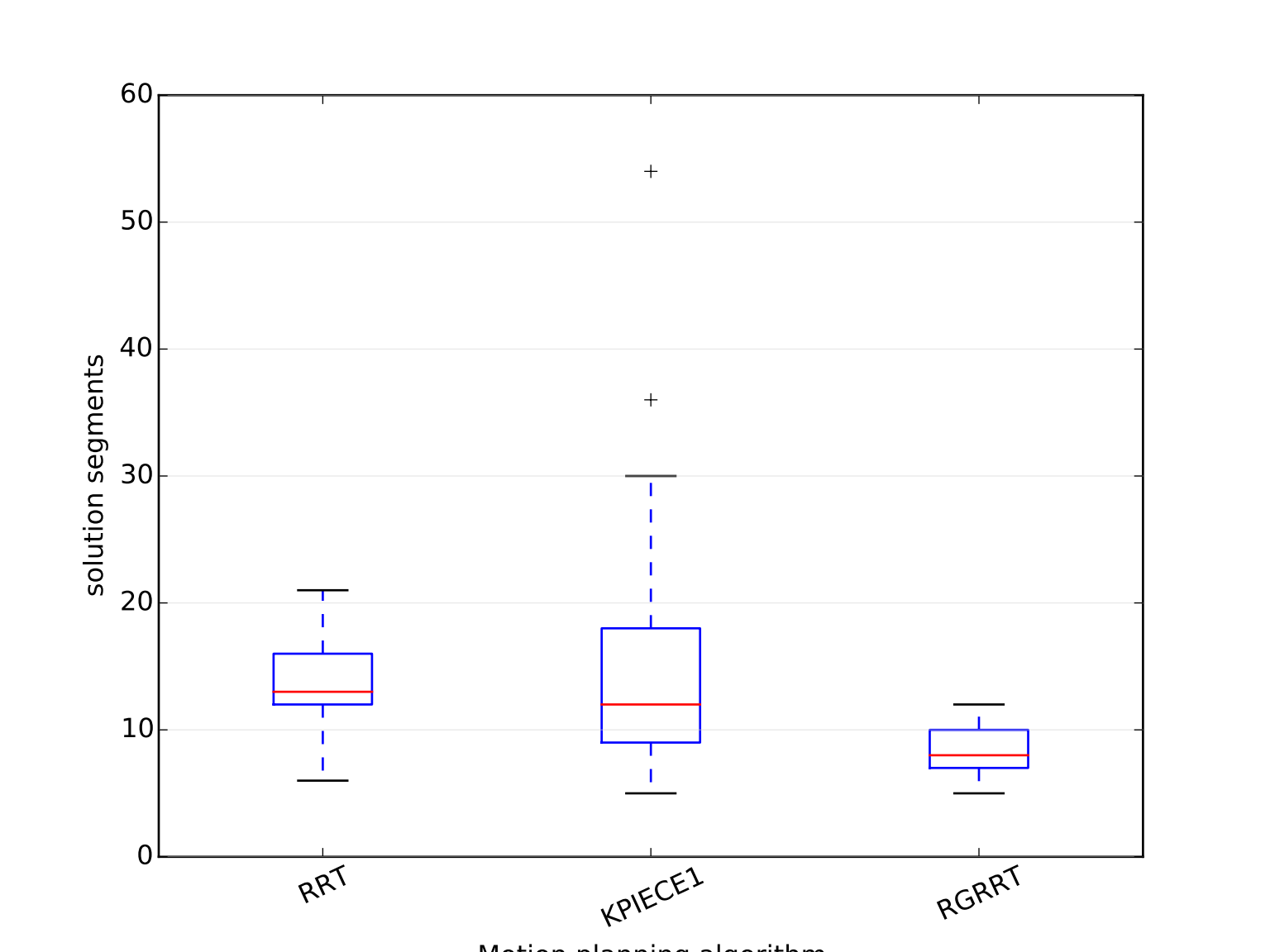

800000
700000
600000
500000
400000
300000
200000
100000
0
graph states
RRT
KPIECE1
RGRRT

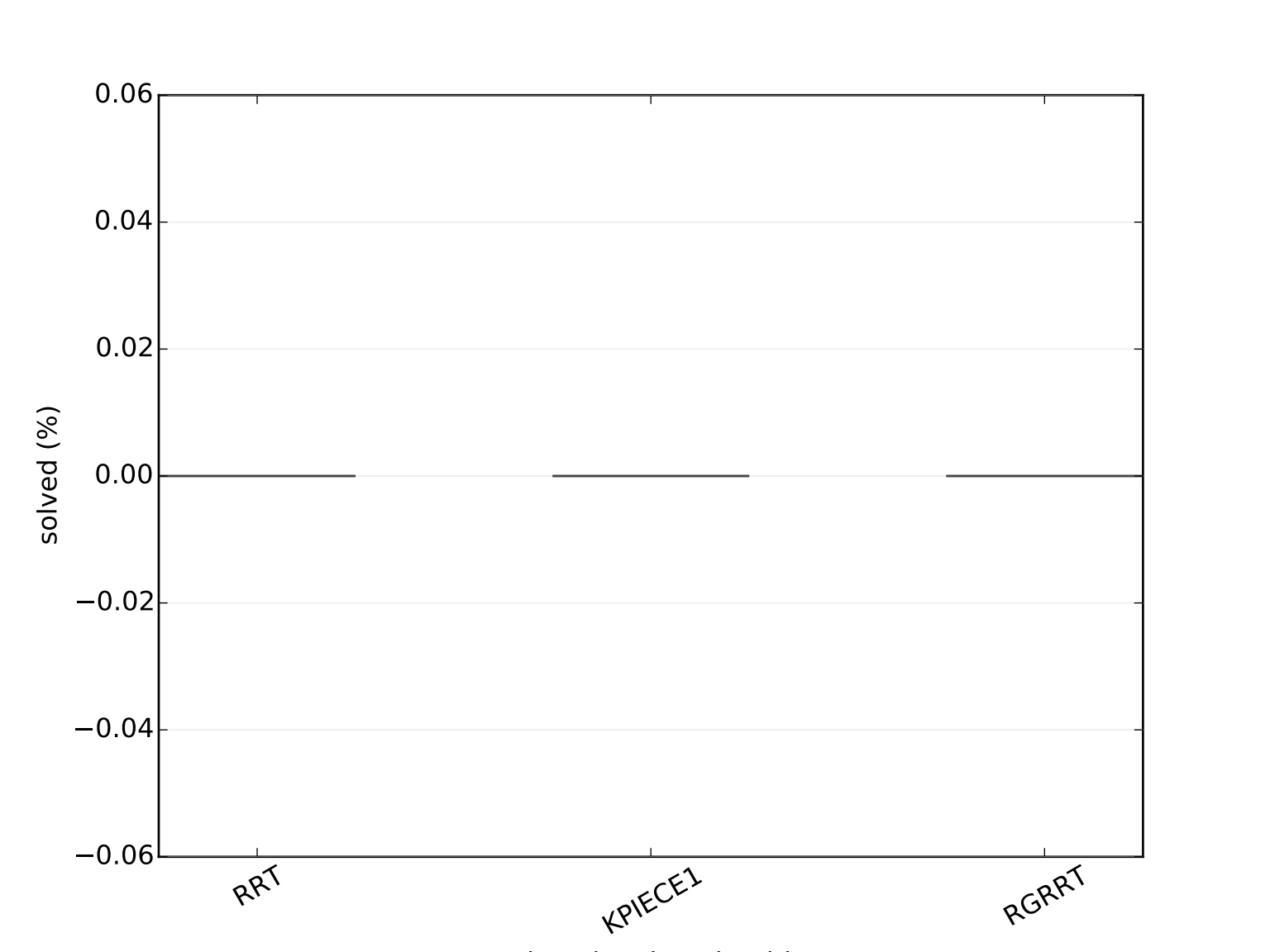

400
350
300
250
200
150
100
50
0
memory
RRT
KPIECE1
RGRRT

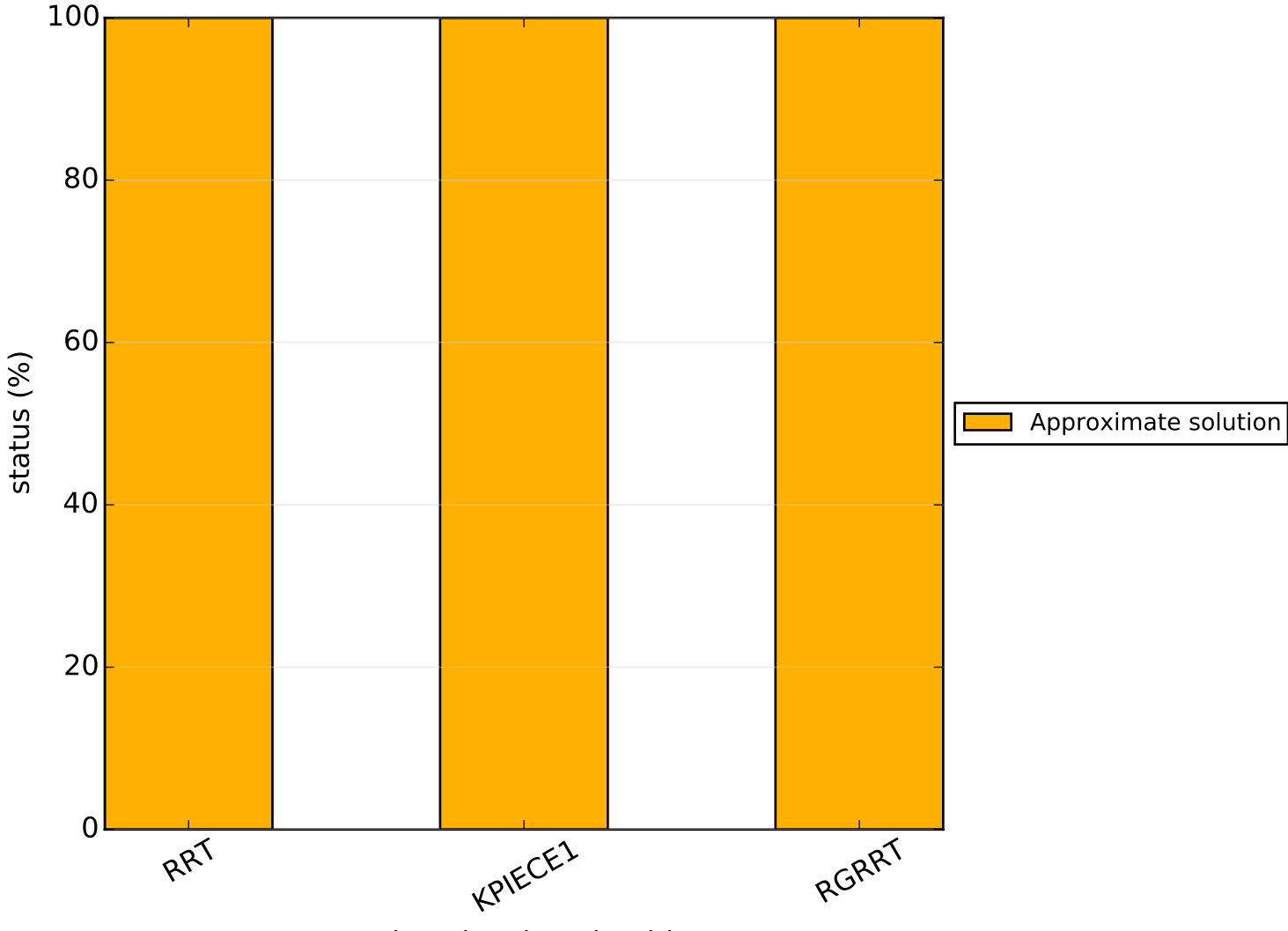

0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
solution clearance
RRT
KPIECE1
RGRRT
Motion planning algorithm

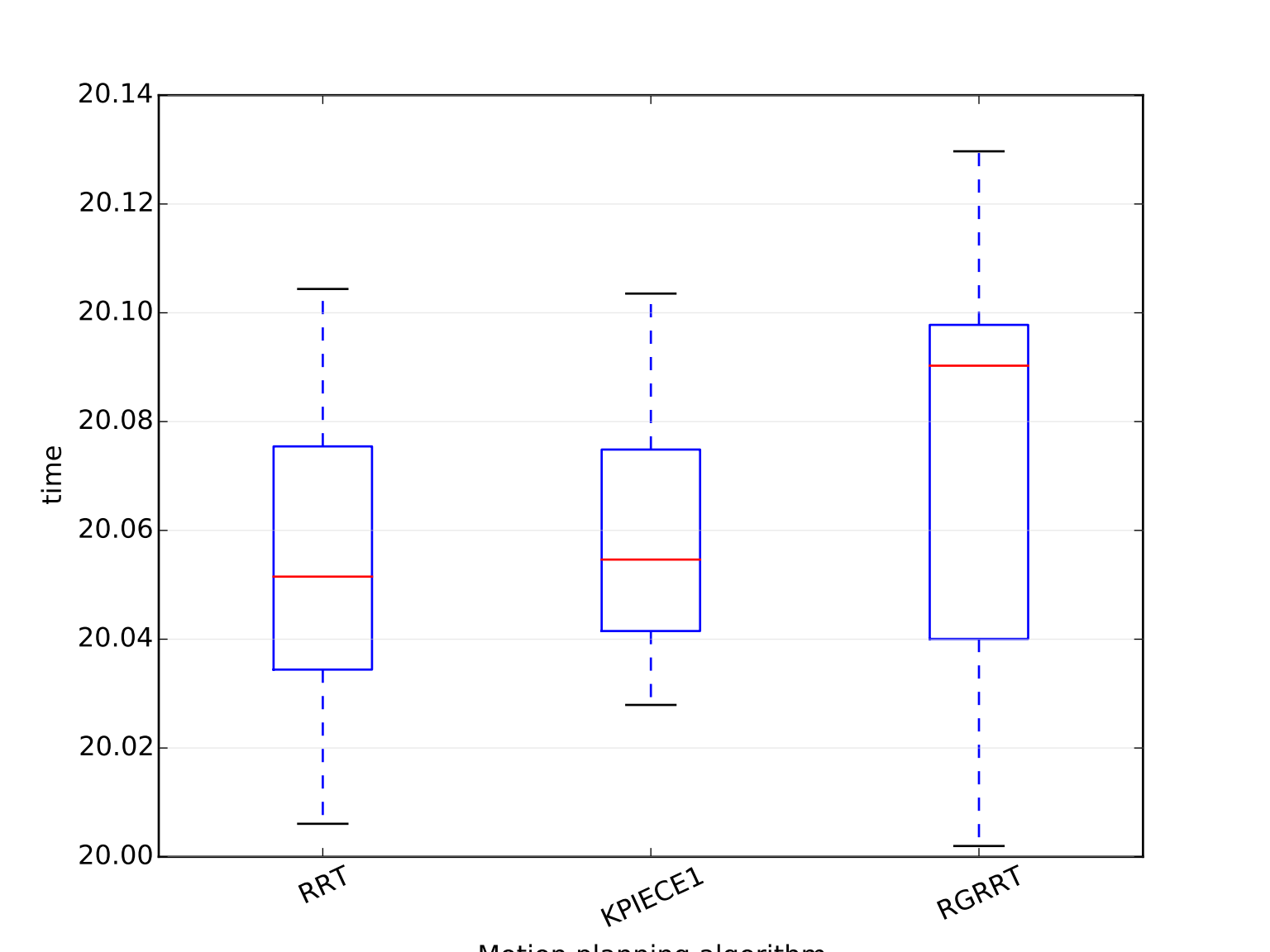

0.35
0.30
0.25
0.20
0.15
0.10
0.05
0.00
solution difference
RRT
KPIECE1
RGRRT
Motion planning algorithm

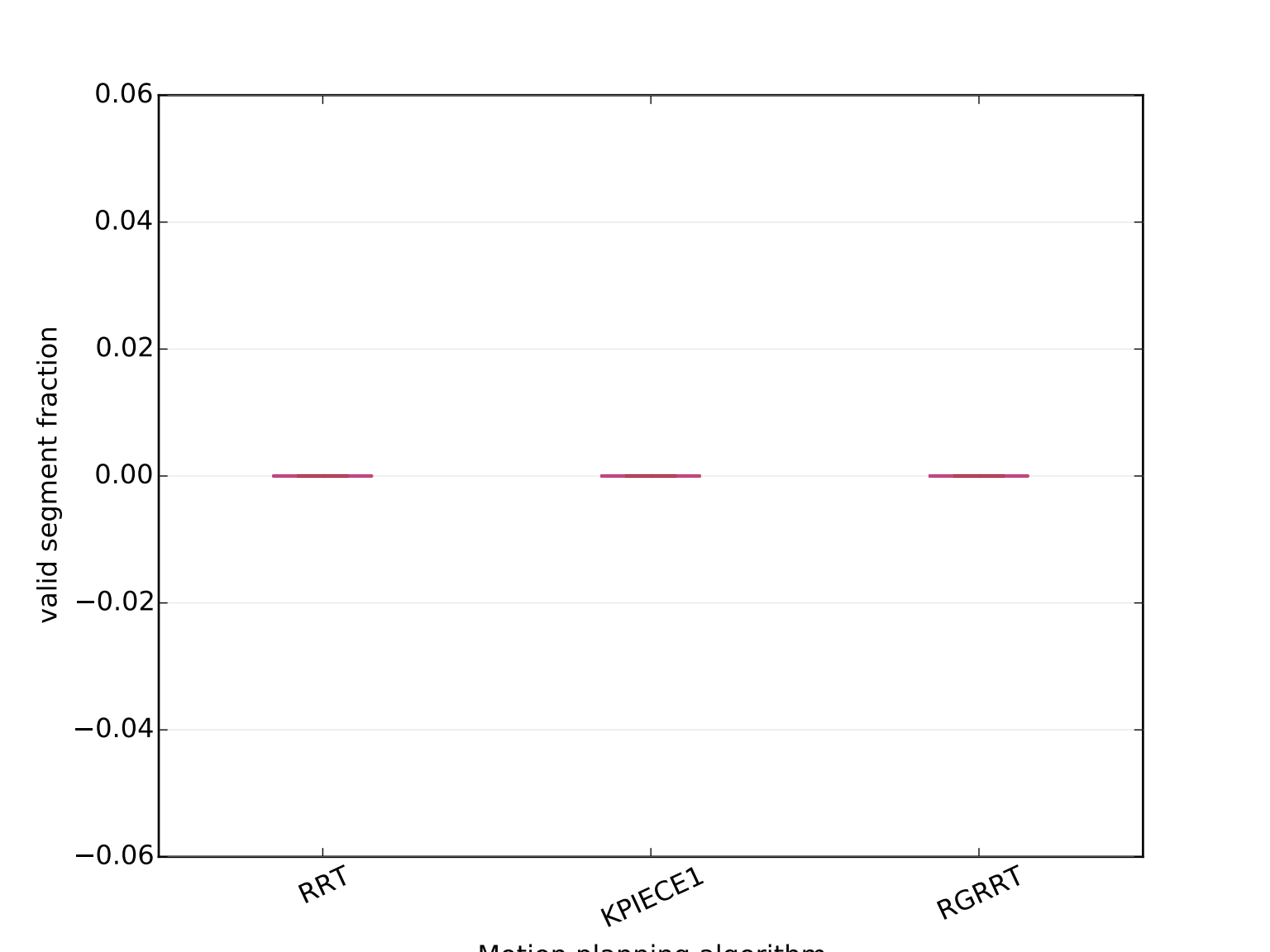

60
50
40
30
20
10
0
solution length
RRT
KPIECE1
RGRRT
Motion planning algorithm


60
50
40
30
20
10
0
solution segments
RRT
KPIECE1
RGRRT


0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
solved (%)
RRT
KPIECE1
RGRRT


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


20.14
20.12
20.10
20.08
20.06
20.04
20.02
20.00
time
RRT
KPIECE1
RGRRT


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

Experiment "_uniform_sampler"

Number of averaged runs: 25

Time limit per run: 20 seconds

Memory limit per run: 10000 MB