Some of the most common algorithms used for motion planning in robotics are broadly divided into two categories,

1. Search based algorithm – A\*
2. Sampling based algorithm – RRT & RRT\*

To reach from the start position to the end position, the robot follows a given path. The state of the robot at any given points along the path can be described using three variables

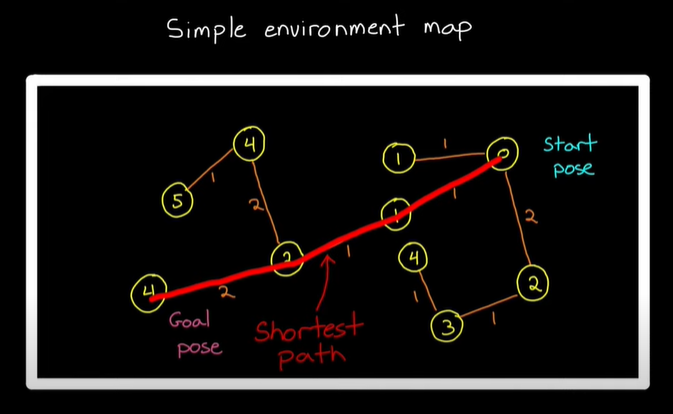
1. X
2. Y
3. Orientation

A path planning problem includes finding the path to reach from point A to point B and is a subset of the motion planning problem. In case of motion planning, a wider set of variables are estimated – velocity, acceleration, angular rotation etc.

Graph based methods to find the path between a start and goal pose

General idea:

* Create nodes in random directions on a graph such that the cost of getting to a node is the distance between the two nodes. The total cost of reaching the end goal would be a total of the lengths between nodes. Randomised points create paths although not the shortest
* In the next iteration create new nodes and keep checking the costs associated with reaching nodes. If a previous node is encountered, compare the total lengths between this new path and the old one and keep only the path with a shorter length.
* In this kind of a search algorithm, only trees (subset of interconnect paths wherein the nodes can connect to other nodes in whatever way possible) are maintained (each node has only one parent) by always keeping the smallest path
* Keep updating and the shortest path is obtained. This kind of search algorithm doesn’t render the shortest path precisely but keeps approaching it as the number of nodes keep approaching infinity
* Generally speaking, this building of trees from random wandering isn’t the best solution and that’s where the graph-based methods of tree building come into picture



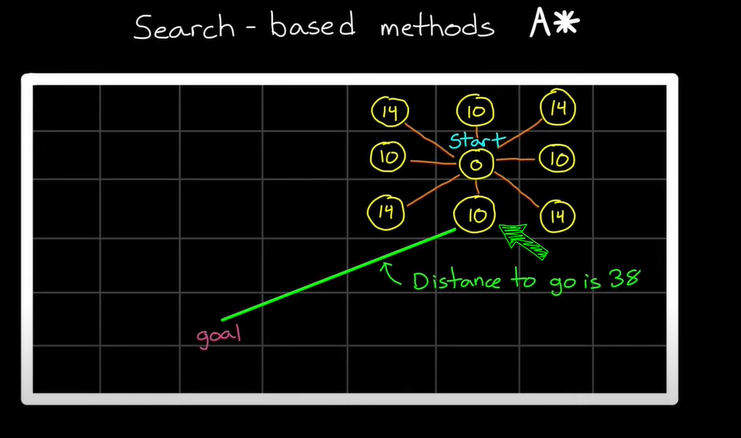
**Search based algorithms**

Build trees by adding nodes in an ordered pattern

* Start with a grid-based occupancy map and create nodes in each cell, the algorithm would then check for the cost that reaching each cell would take
* Keep populating each cell in the grid with a node and calculate and eliminate the paths with greater costs
* When the entire grid is covered, while maintaining the tree structure, the shortest path would be the one with the least cost associated to it
* Optimal path will be generated where the degree of optimal path would depend on the resolution of the grids
* Computationally expensive, since it is a brute force method of finding the more optimal paths

As a result, the A\* algorithm was found out.

* Here everything else remains the same, but instead of having to search through a brute force method, an additional cost is calculated along with the cost of getting to a node
* The total cost in case of the A\* algorithm is the cost to get to the node and the straight-line distance between the node and the end goal.
* As it keeps a track of the distance between the node and the end goal, it chooses a path that is more likely to produce a path with a shorter distance
* As a result, you don’t have to check at every node

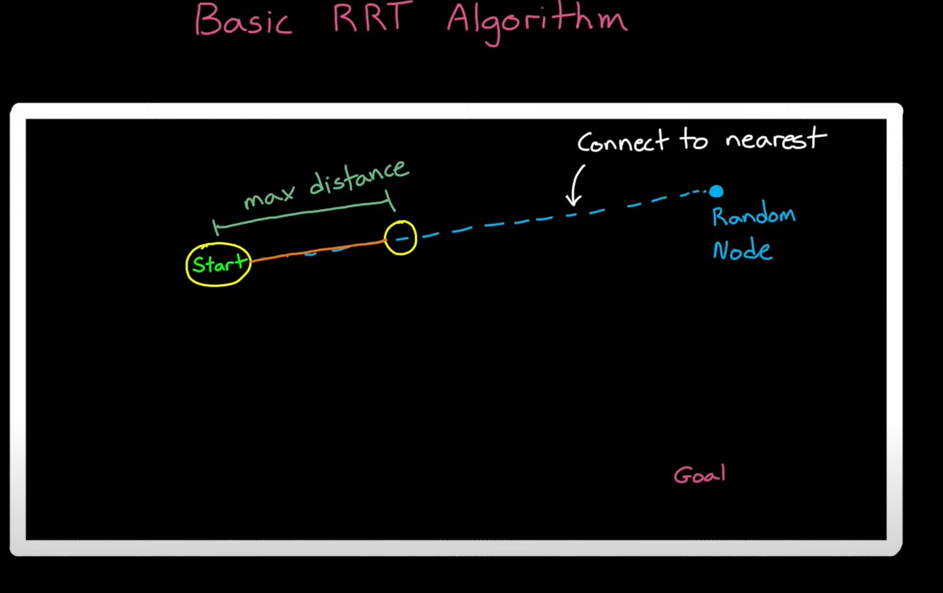


Issue – Computationally intensive if the size and dimensions of the state space increase, and hence the search-based algorithms are generally not preferred. **Hence, sampling-based algorithm**

Rapidly Exploring Random Trees

This algorithm has the following steps,

* Define the start and the end goal points
* Start by randomly creating nodes anywhere on the occupancy map. This node point can be created too far away as compared to the previous point which can cause the path to move away from the goal point, or wander off in a direction that is away from the goal point. Hence, in a RRT algorithm a max distance is defined. Thus, when a new node is created, there might be three situations that might arise,
  + If the new node created is within the max distance from the previous node, it is placed where it is produced
  + If the new node produced is more than the max distance from the previous node, then it is placed at the max distance from the previous node, along the same direction
  + If in any of the two cases, the path between the two nodes passes an obstacle then that node is completely ignored and a next node is created



* The new node created is then joined to an existing node which is closest to the new node. Hence, in such a case there will be a path formed that is rapidly approaching the goal destination.
* Even if there are nodes created away from the goals, the paths they form will keep growing in the opposite direction, leaving the actual optimal paths untouched. Hence, there will always be some paths that will always keep moving towards the goal destination
* Once a single path reaches within a threshold of the goal position, the algorithm stops producing nodes/expanding the trees

RRT\*

In case of the RRT\*, the searching proceeds as follows,

* Random nodes are created on the map and placed based on the maximum distance criterion (if the new node is at a distance greater than the max distance, the new node is placed at the max distance; if not, then the new node is placed where it is created)
* After a particular node is created, the next step in case of the RRT was to join it to the nearest node. This is where RRT\* is different from the RRT algorithm
* Instead of directly attaching it to the nearest node, it looks for a node within a particular search distance that not only keeps the tree structure intact but also reduces the total path length. This means the new node can connect to an old node, even if the old node is not the closest to the new one.

