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[Implementasi Algoritma Best Path Planning Untuk Pencarian](#)

Michael Morin

Implementasi Algoritma Best Path Planning Untuk Pencarian:

Recent Advances in Soft Computing and Data Mining Rozaida Ghazali,Nazri Mohd Nawi,Mustafa Mat Deris,Jemal H. Abawajy,Nureize Arbaiy,2022-05-03 This book unfolds ways to transform data into innovative solutions perceived as new remarkable and meaningful value It offers practical views of the concepts and techniques readers need to get the most out of their large scale research and data mining projects It strides them through the data analytical thinking circumvents the difficulty in deciphering complex data systems and obtaining commercialization value from the data Also known as data driven science soft computing and data mining disciplines cover a broad spectrum an interdisciplinary field of scientific methods and processes The book Recent Advances in Soft Computing and Data Mining delivers sufficient knowledge to tackle a wide range of issues seen in complex systems This is done by exploring a vast combination of practices and applications by incorporating these two domains To thrive in these data driven ecosystems researchers data analysts and practitioners must choose the best design to approach the problem with the most efficient tools and techniques To thrive in these data driven ecosystems researchers data analysts and practitioners must understand the design choice and options of these approaches thus to better appreciate the concepts tools and techniques used   Using Improved Bidirectional A* Algorithm to Achieve Optimal Path Planning 王浩江,2012   **Sampling-based Algorithms for Optimal Path Planning Problems** Sertac Karaman,Massachusetts Institute of Technology. Department of Electrical Engineering and Computer Science,2012 Sampling based motion planning received increasing attention during the last decade In particular some of the leading paradigms such the Probabilistic RoadMap PRM and the Rapidly exploring Random Tree RRT algorithms have been demonstrated on several robotic platforms and found applications well outside the robotics domain However a large portion of this research effort has been limited to the classical feasible path planning problem which asks for finding a path that starts from an initial configuration and reaches a goal configuration while avoiding collision with obstacles The main contribution of this dissertation is a novel class of algorithms that extend the application domain of sampling based methods to two new directions optimal path planning and path planning with complex task specifications Regarding the optimal path planning problem we first show that the existing algorithms either lack asymptotic optimality i e almost sure convergence to optimal solutions or they lack computational efficiency on one hand neither the RRT nor the k nearest PRM for any fixed k is asymptotically optimal on the other hand the simple PRM algorithm where the connections are sought within fixed radius balls is not computationally as efficient as the RRT or the efficient PRM variants Subsequently we propose two novel algorithms called PRM and RRT both of which guarantee asymptotic optimality without sacrificing computational efficiency In fact the proposed algorithms and the most efficient existing algorithms such as the RRT have the same asymptotic computational complexity Regarding the path planning problem with complex task specifications we propose an incremental sampling based algorithm that is provably correct and probabilistically complete i e it generates a correct by design path that

satisfies a given deterministic pt calculus specification when such a path exists with probability approaching to one as the number of samples approaches infinity For this purpose we develop two key ingredients First we propose an incremental sampling based algorithm called the RRG that generates a representative set of paths in the form of a graph with guaranteed almost sure convergence towards feasible paths Second we propose an incremental local model checking algorithm for the deterministic p calculus Moreover with the help of these tools and the ideas behind the RRT we construct algorithms that also guarantee almost sure convergence to optimal solutions **Optimal Path Planning Algorithms in Virtual Environments** Rohayanti Hassan,2006 Optimal Path Planning Algorithm in Virtual Environment Muhammad Shafie Abd. Latiff,2004 **Path Planning Algorithms for Autonomous Vehicles** Mohammad Imran Chowdhury,2022 In real world mission planning the environment can be quite complex and a path planner has thepotential to enable an agent to fulfill its goals in spite of unanticipated events and unexpected situations A sound path planner defines a path starting from a source point and arriving ultimately at a goal point The path planning algorithms for autonomous vehicles AVs are broadly categorized into two sub areas global path planning and local path planning A global path planner employs known information about the operational environment to return a path from the start point to the goal while avoiding fixed obstacles Here obstacles are static such as islands docks ship wrecks et cetera The path is determined prior to the AV s departure In contrast a local path planner recalculates the path returned by the global path planner as needed to avoid unexpected moving obstacles such as ships boats swimmers other AVs et cetera This work initially addresses these issues by working on the most commonly used node basedA algorithm and the sampling based probabilistic road map PRM algorithm The work has found that the A algorithm successfully avoids fixed obstacles but the path is not smooth makes very sharp turns and sometimes comes dangerously close to the obstacle being avoided An issue with the PRM algorithm is that the generated path often is not always optimal id est may be much longer than necessary to avoid the given obstacles Hence initially the work has combined these two approaches in such a way that these deficiencies are remedied In particular the computed path is both smooth and close to optimal In addition this work further improves the PRM A algorithm to maintain a safe distance from fixed obstacles The work subsequently adopted as an alternative the deterministic non heuristic Grassfire GF algorithm GF is conceptually simpler than A and therefore easier to implement For these reasons this research explored replacing A with GF in the hybrid method In addition it was found that the PRM algorithm could be simplified by adopting a different method for creating the roadmap This led to a variant of PRM here dubbed the recursive probabilistic road map r PRM This is conceptually simpler than the original PRM and typically is faster Accordingly this later work presents a novel global planner that employs a combination of three path planners GF Modified Grassfire MGF and r PRM This combination is guaranteed to find a path from any given start point to any given goal point as long as such a path is possible For dealing with the moving obstacles this work first discusses a local path planner using anadaptation of the global path planning

algorithm PRM A It was proposed that this employ the points randomly generated by PRM to construct a path around the moving obstacle However it was found this has the drawback that relying on such points can lead to somewhat erratic behavior Thus this was replaced with a deterministic geometrical approach that achieves the desired effect in a more reliable manner This local planner together with the later global path planner provide a comprehensive path planning system The research has explored the prospect of implementing these algorithms in the well knownMOOS IvP simulation environment PRM A has been ported to MOOS IvP thus enabling one to simulate the use of that planner in controlling an AV in a realistic mission environment This applies only to the global planner however inasmuch as MOOS IvP does not support simulation of the local planner An important feature of the local planner is that it employs a decision logic to determine the beststrategy for avoiding a moving obstacle in particular always routing the AV behind the obstacle rather than in front of or parallel to it whenever this is appropriate Simulations are provided exhibiting the acclaimed behavior For comparison with other systems the simulations include an implementation of the well known D algorithm and the discussion considers additional dynamic path planning systems which like D do not necessarily route the AV behind the moving obstacle **Optimal Path Planning Under Sensing and Motion Uncertainty** Pranav R. Shah,2010 *Optimal Robust Path Planning in General Environments* ,1991 *Search and Coverage Path Planning* Michael Morin,2015 We tackle two different and complementary problems the coverage path planning CPP and the optimal search path OSP The CPP is a main challenge in mobile robotics The OSP is a classic from search theory We first present a review of both problems that highlights their differences and their similarities from the point of view of search coverage operations Both problems are positioned on the continuum of the a priori knowledge on the whereabouts of a search object We then formalize an extension of the CPP we call the CPP with imperfect extended detections CPPIED We present a novel and powerful heuristic algorithm that uses dynamic programming and a traveling salesman TSP reduction We apply the method to underwater minesweeping operations on maps with more than 21 thousand cells We then study a novel constraint programming CP model to solve the OSP We first improve on using the classical objective function found in the OSP definition Our novel objective function involving a single modification of the operators used to compute the probability of success of a search plan leads to a stronger filtering of the probability variables of the model Then we propose a novel heuristic for the OSP the total detection TD heuristic Experiments show that our model along with the proposed heuristic is competitive with problem specific branch and bounds supporting the claim that CP is a good technique to solve search theory problems We finally propose the Markov transition constraint Mtc as a novel modeling tool in CP to simplify the implementation of models based on Markov chains We prove both empirically and theoretically that interval arithmetic is insufficient to filter the probability variables of a single Mtc i e to enforce bounds consistency on these variables Interval arithmetic is the only available tool to filter an Mtc when it is decomposed into individual arithmetic constraints We thus propose an algorithm based on linear programming which is proved to enforce bounds consistency Since

linear programming is computationally expensive to use at each node of the search tree of a CP solver we propose an in between solution based on a fractional knapsack filtering The Mtc global constraint usage is illustrated on a CP model of the OSP **Improving Path Planning Performance by Monitoring Human Decisions** Chee Chian Cheng,2012 Learning by dynamic programming greedy algorithm and graph theory requires prior information like distance and elapse time which are both costs to produce optimal path i e the solution However there is no prior information distance and or elapsed time in most situations until the environment is fully explored There is a need for the system to learn from the agent s i e human s most recent decisions and reproduce the best path i e solution based on the agent s past experiences and the current situation The purpose of this thesis is to propose a solution to improve path planning by observing human decisions in path planning and chunking pieces that are superior to stored paths This includes cumulatively storing the best path chunks based on the agent s experiences **Optimizing Path Planning in 3D Environments with Reinforcement Learning and Sampling-based Algorithms** Wensi Huang,2023 Motion planning also known as path planning is a fundamental problem in the field of robotics and autonomous systems where the objective is to find a collision free path for an agent from a starting position to a goal state Despite the importance of motion planning comparing the performance of various algorithms under the same environment has been rarely explored Furthermore the lack of sufficient evaluation metrics in reinforcement learning RL studies can hinder the understanding of each algorithm s performance This thesis investigates the problem of finding the optimal path in 3D environments using both sampling based and RL algorithms The study evaluates the performance of six algorithms including Rapidly exploring Random Trees RRT RRT Q learning Deep Q Network DQN Trust Region Policy Optimization TRPO and Proximal Policy Optimization PPO while considering the impact of different features in complex 3D spaces Simulation results indicate that RRT outperforms other algorithms in completing a specific path planning task in a 3D grid map The significance of this study lies in providing a comprehensive comparison of different path planning algorithms under the same environment and evaluating them using various metrics This evaluation can serve as a useful guide for selecting an appropriate algorithm to solve specific motion planning problems **An Asymptotically Optimal Path Planning Method with Cubic Bézier Spline** Zifan Fei,2023 This dissertation introduces a novel path planning algorithm for robotics known as Informed SRRT Our algorithm integrates a local planner from SRRT accommodating both external and internal constraints We introduce two extra lines at the B zier spline s endpoints which facilitates the rewiring process A minimum of three state connections need adjustment during rewiring to meet kinematic constraints The effectiveness of the proposed method is demonstrated through various channels Python based simulations Gazebo Rviz a robot simulator and visualization tool in Robot Operating System and real world scenarios In real world experiments the algorithm successfully maneuvered TurtleBot3 past obstacles in the physical map leading to a smooth streamlined and optimal navigation approach Our results reveal that the new algorithm identifies shorter paths than SRRT while achieving

the same number of node sampling iterations However these enhancements come with a trade off as the computational time of this method is slightly higher compared to traditional methods   A Novel Online Any-angle Path Planning Algorithm Paul Oprea,2017   Path Planning Algorithm for Mobile Anchor Based Location in Wireless Sensor Networks ,2015   **On-line Path Planning with Optimal C-space Discretization** Dominik Henrich,Christian Wurll,Heinz Wörn,1998   Path planning algorithms for adverse weather conditions Abhishek Puthige,2022 The treasure hunt problem was introduced to describe the problem of planning the path and measurements of a sensor installed on a ground robot in order to classify multiple targets in an obstacle populated environment The use of conventional path planners like probabilistic roadmaps PRM for this purpose requires prior knowledge of the workspace while other online path planning algorithms rely on the sensor s ability to form a global map and localize itself in it However in unknown workspaces under environmental pressures like fog the information captured by the sensor is extremely local leading to a non convergent global map which subsequently limits the functioning of the algorithms Artificial systems implement decision and control policies to optimize a given cost function on one hand humans use satisficing decision strategies to overcome the limitations of partial information on the other Satisficing strategies lead to solutions that are not always optimal for a given system but which are good enough to meet all its needs at a certain level given the constraints on resources To overcome the limitations of the current artificial systems this work aims to create the building blocks for an adaptive heuristic path planner which efficiently tackles the treasure hunt problem in unknown workspaces under environmental pressures Two different path planners that mimic satisficing strategies have been simulated With the results of this work adaptive heuristic path planners can further be developed which will improve autonomous area exploration and efficiently solve the treasure hunt problem
     Multi-Criteria Path Planning with Terrain Visibility Constraints Michael Morin,2010 Comment utiliser la th orie de la recherche et la planification de chemins pour formuler et r soudre un probl me de d tection dans le contexte de la recherche et sauvetage en milieu terrestre consid rant des aspects pratiques tels que les contraintes de visibilit d coulant du terrain Pour r pondre cette question nous pr sentons une nouvelle formulation introduisant les contraintes de visibilit du chercheur le probl me de planification du chemin optimal du chercheur avec visibilit ou OSPV De plus nous pr sentons une extension multicrit re du probl me Dans un premier temps l efficacit du plan de recherche est quantifi e par la probabilit de retrouver l objet recherch un programme en nombres entiers mixte est compar Ant Search notre adaptation de l optimisation par colonies de fourmis Ensuite l extension multicrit re int gre les aspects de s curit du chercheur et de complexit du plan Ant Search est alors tendu pour introduire Pareto Ant Search et Lexicographie Ant Search   **Probablistic Path Planning** Petr Švestka,Markus Hendrik Overmars,1995

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