

# Asymptotically Optimal Motion Planning

RRT\* Introduction

## RRT\*: Main idea

RRT\* differs from RRT in two ways:

**Change 1:** Each new node connects to the **best** nearby parent, determined by the new node's distance to the root. Not necessarily the node that was nearest neighbor.

**Change 2:** For each new node, check nearby nodes to see if any would have smaller distances with the new node as their parent. If so, **rewire** the tree.