Create a robot and obstacles, add start/end points , make the figure of the robot and pathplan in one figure, set axis limits and run the RRT STAR

Is n in the range of the path nodes?

Set a flag true and calcaulate the new target

Is the flag true?

Calculate speed, steer and if the robot is close to the target

Is the robot far from the tsrget

Keep the flag true

Make the flag false

NO

NO

NO

YES

YES

YES