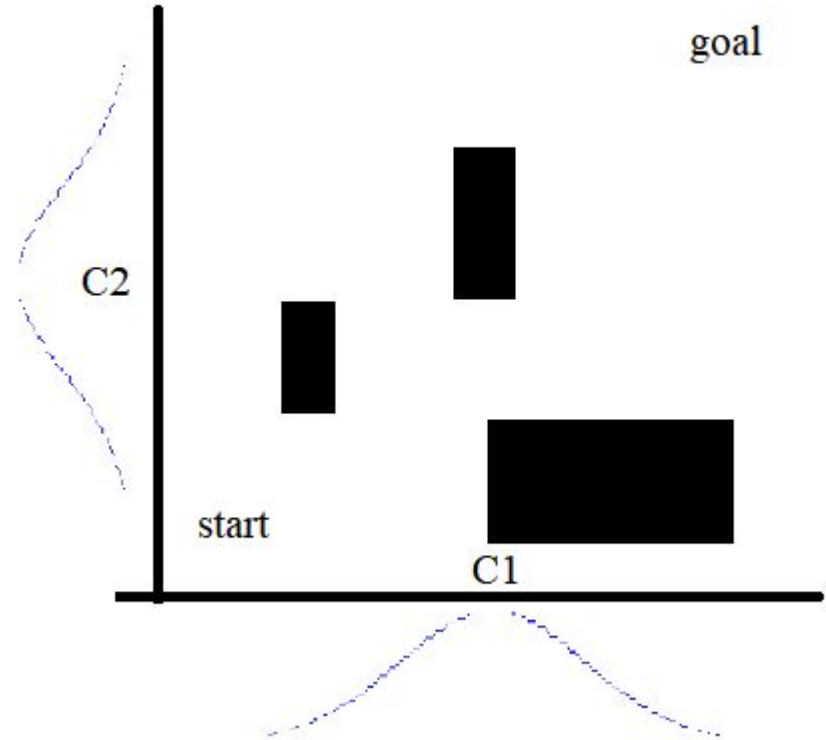


Group 2

Marco Schouten, Zhenlin Zhou

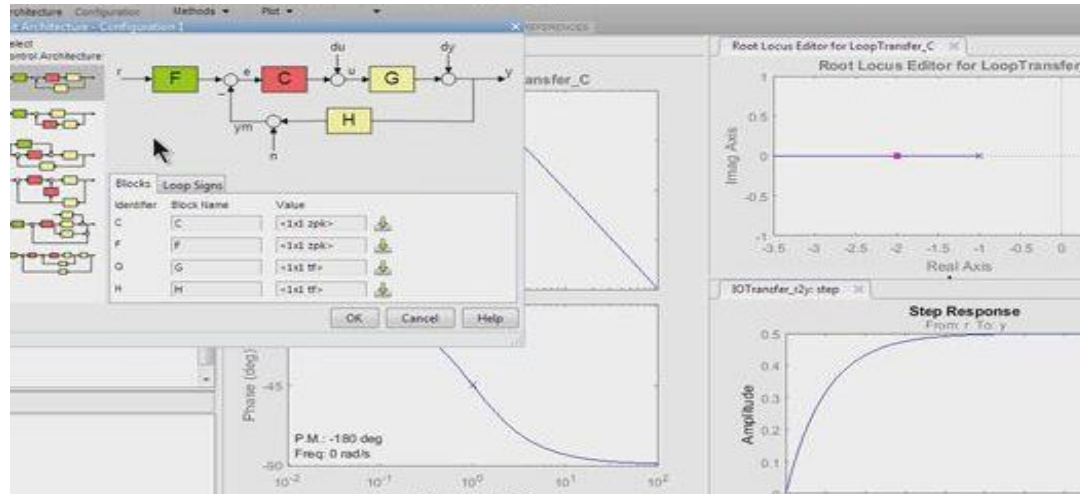
Stage 1: path planning

- Heuristic used for RRT*
convergence:
sampling with gaussians with
centers halfway between start and
goal
- Code still needs some debugging



Stage 2: Vehicle controller

- Closed loop feedback control
- MATLAB (Control systems toolbox)
- converting waypoints to optimal reference signal for each vehicle model



Progress status week 5.

What I did

- wrote code
- trying to design and integrate MATLAB controller

Progress

- Planned Time spent: 40%
- Actual Time spent: 35%
- Actual Progress: 30%
- Risk of not completing assignment: 10%

