Module 6: Questions

1. What would be included in a map for a drone delivery robot that needs to transport packages?
2. What differentiates planning for environments that involve many interacting agents from single agent planning?
3. What is the term that describes artificially increasing the size of obstacles in a map?
4. Briefly describe the trade-off that robots face when they have an incomplete map.
5. What is the requirement for a heuristic function to be admissible?
6. What can happen if a heuristic is in-admissible?
7. How does A* decide which node to explore?
8. When will a node be added to the OpenSet in A*?
9. How is the path reconstructed after running A*?
10. What would happen if A* only considered the heuristic function when deciding which node to explore?