Robotics Practical Check Table:

Part 1		Done?
Completeness	A goal-connecting path can be found between any pair of locations in the displayable region.	
Output	The output shows development of the planned and executed paths.	
Efficiency	The number of moves made and the lengths and total turns of the paths formed by each approach is reported as per the spec.	
Move parameters	The principles for setting them is reported.	
Smoothing	Description of how the travel paths could be smoothed to prevent spinning on the spot as per the spec.	
Planner superiority	Preference given for one of the planners with reasons.	
Part 2		
Output	The output shows development of the planned and executed paths navigating around obstacles.	
Efficiency	As for Part 1, but across a range of obstacle courses.	
Global map and local sensing	Based on theory and a select range of obstacle courses, problems for local sensing reported and compared with a global map.	
Planner superiority	Preference given for one of the planners with reasons.	
Enhancements	Described, implemented, and reported.	
Overview Question	Answered.	
Code and documentation for Parts 1& 2	Commented source code and jar file supplied. Sufficient I/O behaviour shown in report and/or run examples. Programming working and enhancements statement. Word limit adhered to. Screen snapshots for compiling and running. Documentation is clear upon read-through Documentation appears comprehensive upon read-through Documentation shows understanding and effort upon read-through.	