- **Mixing of int32 and int64 in the API specification**
- **Rely on storage service to support consistency model**
  External user will not worry about the versioning
- **Obstacle definition**
  a. Encapsulates the dimensions (height/width) in another object (just like we encapsulated coordinates. Don't call it height)
  b. Name the "type" of the object (e.g., rectangle) so you can parse this differently
- **Don't include x,y values**
- **Limitations on parameters**
  a. Do we want negative problem numbers
  b. Limits on latitude and longitude
  c. Can dimension of an obstacle be negative
- **Server indicates that it has an internal error when trying to find a path on the default problem.**
  This likely indicates that your default problem isn't a well-defined problem. For example, I don't think the boundary makes sense in that default problem - how can the boundary be defined (legally) by only a single point?
- **Didn't address item (d)**
  Provide an implementation that efficiently computes paths while the robot is discovering obstacles as it moves. This will almost certainly require storage of "intermediate" computational results - and these would be stored in the persistent storage layer.
- **Graphical client**

https://ldevr2t1.github.io./
https://github.com/bowei437/Round3_Team2