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MILESTONE update:

1) Simulator setup already in HW3.
   - Tried to fix the link radius not changing in visualization issue.
   - Could not find any input to the robot in Peter Corke's toolbox class which can change the visualization.
   - Since it is not a blocking issue, we will ignore it.
2) Figured out the theory and practical parts (the functions to implement) of different sampling strategies
3) Implemented different sampling strategies which are working fine
   - Uniform
   - Gaussian
   - Bridge Sampling.
4) Path planning algorithms already implemented:
   - PRM
   - RRT
5) Multiple obstacles added with their locations changed from HW3 default configuration to new configuration.
6) GIT setup to collaborate efficiently
7) Explored some path smoothing algorithms and related concepts from https://www.ncbi.nlm.nih.gov/pmc/articles/PMC6165411/ Pages 1-4 out of 30 read.
8) Explored different functions in MATLAB for performing path smoothing using Polynomial Interpolation. Like polyfit, polyval, and interp1.