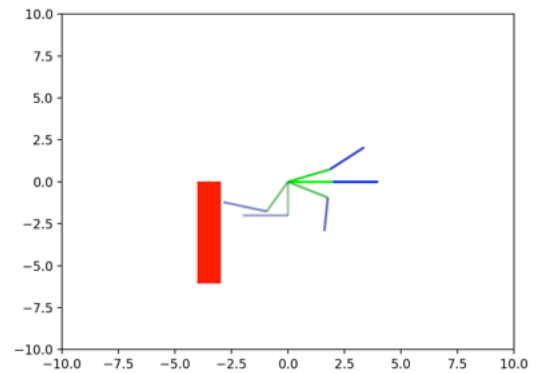
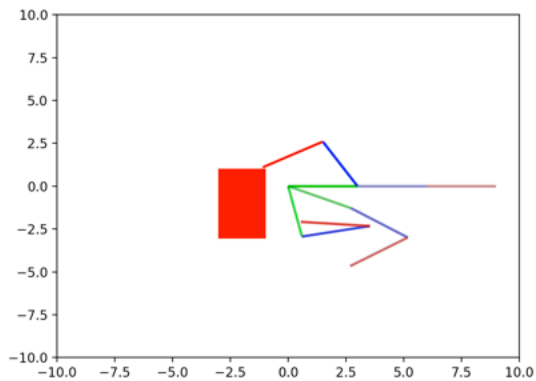


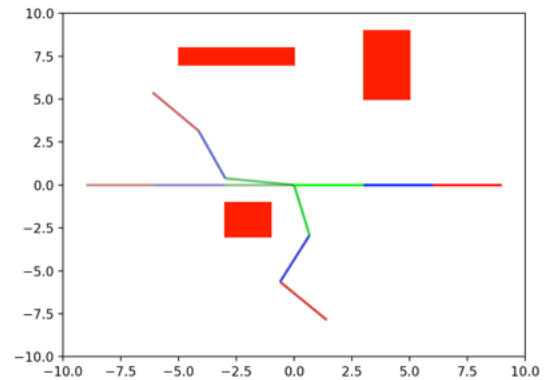
Robot arm motion for 2 arm segments



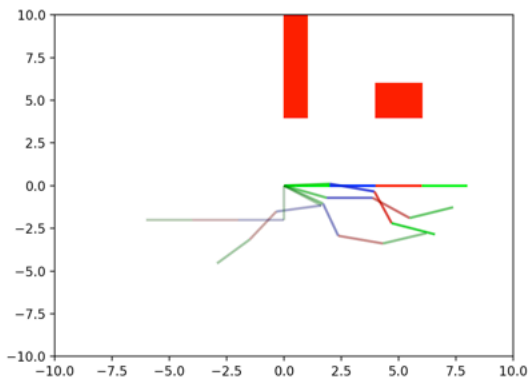
Robot arm motion for 2 arm segments



Robot arm motion for 3 arm segments



Robot arm motion for 3 arm segments



Robot arm motion for 4 arm segments

```
start = (0, 0, 0, 0)
goal = (3*math.pi/2, 3*math.pi/2, 0, 0)
lengths = [2, 2, 2, 2]
obstacles = [[0, 4, 1, 6], [4, 4, 2, 2]]
test_arm = Workspace(start, lengths, obstacles)
#test_arm.generate_graphic()

test_prm = PRM(test_arm)
#test_prm.build_roadmap(10)
test_prm.prm(40, start, goal)
#test_arm.generate_graphic()
```