Finished loading the parking lot environment....

Info: RRTstar: No optimization objective specified. Defaulting to optimizing path length for the allowed planning time.

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 40.62 in 29 iterations (15 vertices in the graph)

Info: RRTstar: Created 287 new states. Checked 41328 rewire options. 1 goal states in tree. Final solution cost 30.727

Info: Solution found in 4.945110 seconds

Info: SimpleSetup: Path simplification took 0.299097 seconds and changed from 6 to 2 states

found a solution

Info: RRTstar: No optimization objective specified. Defaulting to optimizing path length for the allowed planning time.

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 32.42 in 12 iterations (8 vertices in the graph)

Info: RRTstar: Created 304 new states. Checked 46360 rewire options. 1 goal states in tree. Final solution cost 32.416

Info: Solution found in 5.696926 seconds

Info: SimpleSetup: Path simplification took 0.301344 seconds and changed from 6 to 2 states

found a solution

-----------------------------------------------

------------------------ checking ------------------------

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0

1

Collisions at t= 21

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 20.43 in 6 iterations (5 vertices in the graph)

Info: RRTstar: Created 285 new states. Checked 40755 rewire options. 1 goal states in tree. Final solution cost 20.430

Info: Solution found in 5.037776 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 22

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 28.34 in 41 iterations (19 vertices in the graph)

Info: RRTstar: Created 298 new states. Checked 44551 rewire options. 1 goal states in tree. Final solution cost 26.230

Info: Solution found in 5.461310 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 23

wait for...8

------------------------ checking ------------------------

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------------------------ checking ------------------------

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------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 32

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 22.66 in 8 iterations (7 vertices in the graph)

Info: RRTstar: Created 272 new states. Checked 37128 rewire options. 1 goal states in tree. Final solution cost 22.662

Info: Solution found in 5.260401 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 33

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 23.51 in 18 iterations (12 vertices in the graph)

Info: RRTstar: Created 298 new states. Checked 44551 rewire options. 1 goal states in tree. Final solution cost 23.509

Info: Solution found in 5.679253 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 34

wait for...9

------------------------ checking ------------------------

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------------------------ checking ------------------------

0

1

Collisions at t= 44

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 19.19 in 19 iterations (11 vertices in the graph)

Info: RRTstar: Created 285 new states. Checked 40755 rewire options. 1 goal states in tree. Final solution cost 19.192

Info: Solution found in 5.317584 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 45

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 24.97 in 32 iterations (18 vertices in the graph)

Info: RRTstar: Created 315 new states. Checked 49770 rewire options. 1 goal states in tree. Final solution cost 24.106

Info: Solution found in 6.406115 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 46

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 23.93 in 17 iterations (10 vertices in the graph)

Info: RRTstar: Created 319 new states. Checked 51040 rewire options. 1 goal states in tree. Final solution cost 19.883

Info: Solution found in 6.463001 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 47

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 44.79 in 50 iterations (22 vertices in the graph)

Info: RRTstar: Created 276 new states. Checked 38226 rewire options. 1 goal states in tree. Final solution cost 21.057

Info: Solution found in 5.064301 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 48

wait for...6

------------------------ checking ------------------------

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------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 55

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 25.94 in 24 iterations (16 vertices in the graph)

Info: RRTstar: Created 297 new states. Checked 44253 rewire options. 1 goal states in tree. Final solution cost 20.196

Info: Solution found in 5.303213 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 56

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 23.43 in 22 iterations (11 vertices in the graph)

Info: RRTstar: Created 285 new states. Checked 40755 rewire options. 1 goal states in tree. Final solution cost 20.915

Info: Solution found in 6.375409 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 57

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 32.96 in 16 iterations (12 vertices in the graph)

Info: RRTstar: Created 319 new states. Checked 51040 rewire options. 1 goal states in tree. Final solution cost 23.384

Info: Solution found in 6.173500 seconds

found a solution

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 59

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 42.35 in 21 iterations (11 vertices in the graph)

Info: RRTstar: Created 306 new states. Checked 46971 rewire options. 1 goal states in tree. Final solution cost 25.198

Info: Solution found in 5.910985 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 60

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 19.49 in 25 iterations (11 vertices in the graph)

Info: RRTstar: Created 297 new states. Checked 44253 rewire options. 1 goal states in tree. Final solution cost 19.487

Info: Solution found in 5.461137 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 61

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 19.91 in 29 iterations (10 vertices in the graph)

Info: RRTstar: Created 277 new states. Checked 38503 rewire options. 1 goal states in tree. Final solution cost 19.913

Info: Solution found in 5.378970 seconds

found a solution

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 63

wait for...6

------------------------ checking ------------------------

------------------------ checking ------------------------

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0

1

Collisions at t= 70

wait for...3

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 74

wait for...6

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 81

wait for...3

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 85

wait for...6

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

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------------------------ checking ------------------------

0

1

Collisions at t= 92

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 45.54 in 64 iterations (39 vertices in the graph)

Info: RRTstar: Created 291 new states. Checked 42486 rewire options. 1 goal states in tree. Final solution cost 45.539

Info: Solution found in 5.260443 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 93

wait for...2

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 96

wait for...7

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

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------------------------ checking ------------------------

0

1

Collisions at t= 104

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 20.70 in 18 iterations (9 vertices in the graph)

Info: RRTstar: Created 293 new states. Checked 43071 rewire options. 1 goal states in tree. Final solution cost 19.800

Info: Solution found in 5.416119 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 105

wait for...1

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 107

wait for...8

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

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------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 116

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 24.99 in 39 iterations (14 vertices in the graph)

Info: RRTstar: Created 284 new states. Checked 40470 rewire options. 1 goal states in tree. Final solution cost 19.528

Info: Solution found in 5.185804 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 117

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 22.03 in 22 iterations (10 vertices in the graph)

Info: RRTstar: Created 319 new states. Checked 51040 rewire options. 1 goal states in tree. Final solution cost 22.026

Info: Solution found in 6.701482 seconds

found a solution

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 119

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 20.72 in 42 iterations (15 vertices in the graph)

Info: RRTstar: Created 285 new states. Checked 40755 rewire options. 1 goal states in tree. Final solution cost 20.718

Info: Solution found in 4.758827 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 120

wait for...7

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

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------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 128

wait for...2

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 131

wait for...7

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 139

wait for...2

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 142

wait for...7

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 150

wait for...2

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 153

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 18.84 in 4 iterations (5 vertices in the graph)

Info: RRTstar: Created 310 new states. Checked 48205 rewire options. 1 goal states in tree. Final solution cost 18.840

Info: Solution found in 6.150062 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 154

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 25.62 in 44 iterations (23 vertices in the graph)

Info: RRTstar: Created 304 new states. Checked 46360 rewire options. 1 goal states in tree. Final solution cost 23.360

Info: Solution found in 5.645560 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 155

wait for...5

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 161

wait for...4

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 166

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 31.78 in 32 iterations (13 vertices in the graph)

Info: RRTstar: Created 264 new states. Checked 34980 rewire options. 1 goal states in tree. Final solution cost 23.340

Info: Solution found in 4.743356 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 167

wait for...4

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 172

wait for...5

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 178

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 22.71 in 12 iterations (6 vertices in the graph)

Info: RRTstar: Created 284 new states. Checked 40470 rewire options. 1 goal states in tree. Final solution cost 21.700

Info: Solution found in 5.016875 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 179

wait for...3

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 183

wait for...6

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 190

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 33.57 in 27 iterations (12 vertices in the graph)

Info: RRTstar: Created 274 new states. Checked 37675 rewire options. 1 goal states in tree. Final solution cost 21.841

Info: Solution found in 5.125604 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 191

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 25.25 in 18 iterations (14 vertices in the graph)

Info: RRTstar: Created 315 new states. Checked 49770 rewire options. 1 goal states in tree. Final solution cost 24.577

Info: Solution found in 6.073679 seconds

found a solution

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 194

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 19.69 in 7 iterations (7 vertices in the graph)

Info: RRTstar: Created 321 new states. Checked 51681 rewire options. 1 goal states in tree. Final solution cost 19.690

Info: Solution found in 5.902976 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 195

wait for...9

------------------------ checking ------------------------

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0

1

Collisions at t= 206

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 31.74 in 14 iterations (10 vertices in the graph)

Info: RRTstar: Created 281 new states. Checked 39621 rewire options. 1 goal states in tree. Final solution cost 19.307

Info: Solution found in 4.921053 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 207

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 30.98 in 19 iterations (11 vertices in the graph)

Info: RRTstar: Created 302 new states. Checked 45753 rewire options. 1 goal states in tree. Final solution cost 23.718

Info: Solution found in 5.490882 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 208

wait for...8

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

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------------------------ checking ------------------------

0

1

Collisions at t= 218

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 27.39 in 32 iterations (14 vertices in the graph)

Info: RRTstar: Created 274 new states. Checked 37675 rewire options. 1 goal states in tree. Final solution cost 19.241

Info: Solution found in 5.038072 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 219

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 36.47 in 14 iterations (11 vertices in the graph)

Info: RRTstar: Created 285 new states. Checked 40755 rewire options. 1 goal states in tree. Final solution cost 24.968

Info: Solution found in 5.400264 seconds

found a solution

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 221

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 17.77 in 39 iterations (18 vertices in the graph)

Info: RRTstar: Created 291 new states. Checked 42486 rewire options. 1 goal states in tree. Final solution cost 17.765

Info: Solution found in 5.171866 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 222

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 19.57 in 16 iterations (10 vertices in the graph)

Info: RRTstar: Created 330 new states. Checked 54615 rewire options. 1 goal states in tree. Final solution cost 19.567

Info: Solution found in 6.559423 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 223

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 17.77 in 15 iterations (10 vertices in the graph)

Info: RRTstar: Created 300 new states. Checked 45150 rewire options. 1 goal states in tree. Final solution cost 17.765

Info: Solution found in 5.401230 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 224

wait for...4

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 229

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 19.14 in 23 iterations (15 vertices in the graph)

Info: RRTstar: Created 311 new states. Checked 48516 rewire options. 1 goal states in tree. Final solution cost 19.136

Info: Solution found in 5.835611 seconds

found a solution

------------------------ checking ------------------------

0

1

Collisions at t= 230

wait for...4

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 235

wait for...5

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

------------------------ checking ------------------------

0

1

Collisions at t= 241

start to replan......

Info: RRTstar: Started planning with 1 states. Seeking a solution better than 0.00000.

Info: RRTstar: Initial k-nearest value of 45

Info: RRTstar: Found an initial solution with a cost of 21.55 in 8 iterations (6 vertices in the graph)

Info: RRTstar: Created 291 new states. Checked 42486 rewire options. 1 goal states in tree. Final solution cost 21.554

Info: Solution found in 5.483345 seconds

found a solution

------------------------ checking ------------------------

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C:\Users\haohua\Documents\GitHub\ece4095-parking-system-code\toy\AutoParkingSimulator\Debug\AutoParkingSimulator.exe (process 7444) exited with code 0.

To automatically close the console when debugging stops, enable Tools->Options->Debugging->Automatically close the console when debugging stops.

Press any key to close this window . . .