Code Explanation

Scripts to modify

astar.m	A* motion planner
rrt.m	RRT motion planner
rrtstar.m	(Optional) RRT* motion planner

Following scripts are useful for implementing the planner

runtest.m	Run different planners
collcheckstline.m	Collision check all points along a straight line between two 2D points
checkLimits.m	Checks if the 2D point robot is within the map
map1.txt	A small map
map2.txt	A big map
bresenham.m	Implements Bresenham's line algorithm. You do not have to use this directly