ME766A: Robot Motion Planning
Assignment-4: Rapidly-exploring Random Tree(RRT) Simulation
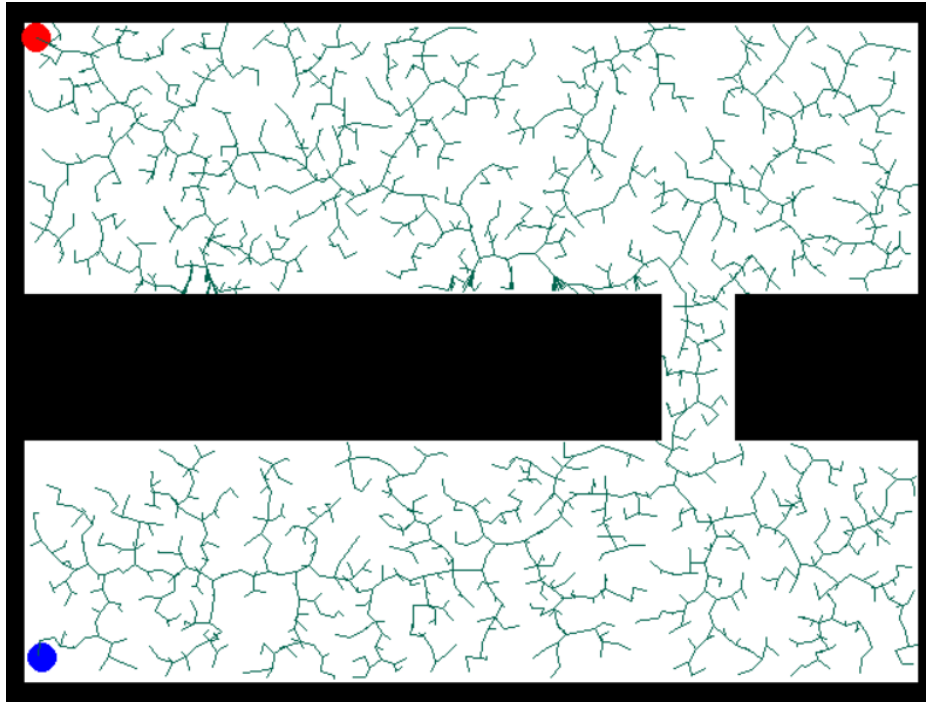*Name: Kartikeya Gupta*
Roll No: 190420

Figure 1: Robot workspace and network of paths simulated using RRT
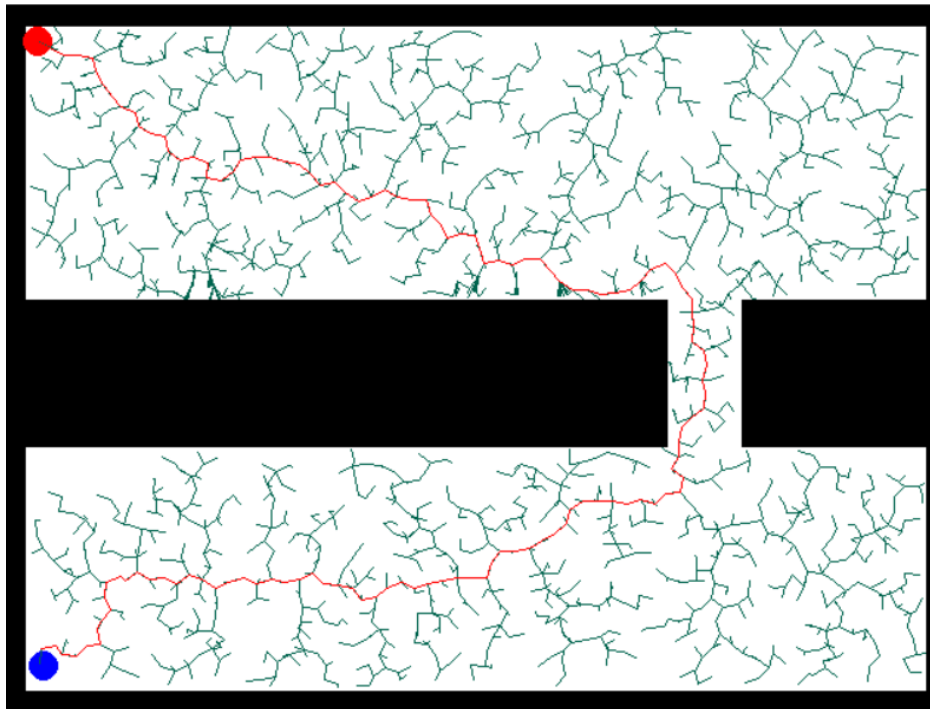

Figure 2: Final path connecting the goal and start point of the robot (indicated with red)