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

*A picture containing text

Description automatically generated*

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

*A map of a city

Description automatically generated with low confidence*

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