Assignment – implement bi-directional RRT* (Due on March 12 by noon)

- Paper
  - Karaman, S. and Frazzoli, E., 2010. Incremental sampling-based algorithms for optimal motion planning. *Robotics Science and Systems VI*, *104*, p.2.

- A youtube video that can help you learn
  - https://www.youtube.com/watch?v=JeEk_CWcRFI

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- Requirement
  - You may use the same terrain map for the implementation of ANA*
  - Implementation python
  - You may find RRT* code online
    - https://www.linkedin.com/pulse/motion-planning-algorithm-rrt-star-python-code-md-mahbubur-rahman/ -- I haven't tested this code. Use with caution
  - Bi-directional RRT*
    - One connect tree + one extend tree
  - After implementation, test your code for 10 time and show statistics for
    - Time (individual and average), Path length
    - Comparison with RRT, RRT*