Project 2 Notes from Info Session

Np.random.rand()

- Will be used within rrt

There are functions that grab the nearest nodes

- Etend?
- N_node = n+step

Polygonenvironmen has

Flags = _Trapped, _Advanced, _REACHED

RRT connect

- Choose a small enough epsilon

RRT bi-directional

For bi-directional, store one as an “A” tree, and one as a “B” tree

PPRM

Straight line planner is on us to implement.

- We need to plan a path between A and B, and return a flag if the connection isn’t possible.
    - There’s an extra credit problem to build an RRT between A and B
- Take ~100 samples, if all samples are NOT in collision, then we’re good
    - You can return the roadmap, AND the plan
- If you can’t find a plan, add more samples until you can find a plan there.