

## Lab3 Report Team-8-good

### Problem 5:

Compared to the previous results using “\_get\_random\_sample\_near\_goal”, the results obtained by problem 5 are as **precise** as a scalpel in a well-trained surgeon. It took less detour but move towards the goal ( the can).

### Problem 6:

If the probability of getting a random sample near the goal increases to 1.0, the rrt tree will extend directly to the goal point. However, if there is an obstacle between the goal point and the start point, the RRT tree will get stuck and stop extending.

