Autonomous

Car

Robot

1. Goal:

Navigate the environment while avoiding obstacles.



2. Methods (env.)

env.get_sensor_forward_value()
env.get_sensor_right_value()
env.get_sensor_left_value()
env.step(action)

3. Dictionary

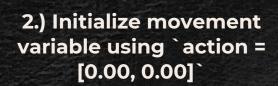
sensor_readings = {
 "Forward": forward,
 "Right": right,
 "Left": left

4. Direction

greatest_direction = max(sensor_readings, key=sensor_readings.get)



1.) Mimicking real-world autonomous driving, start an infinite while loop using `while True:`





- 5.) Execute the action using env.step(action) to apply the movement
- 6.) To avoid rapid, unrealistic movement, introduce a small delay after each step using 'time.sleep(0.0001)`



- 3.) Retrieve sensor values for forward, left, and right, and store them each in their own variable
 - 4.) Decide Action -->
 - If left has more space, turn left.
 - If right has more space, turn right.
 - If forward is clear, move forward.

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