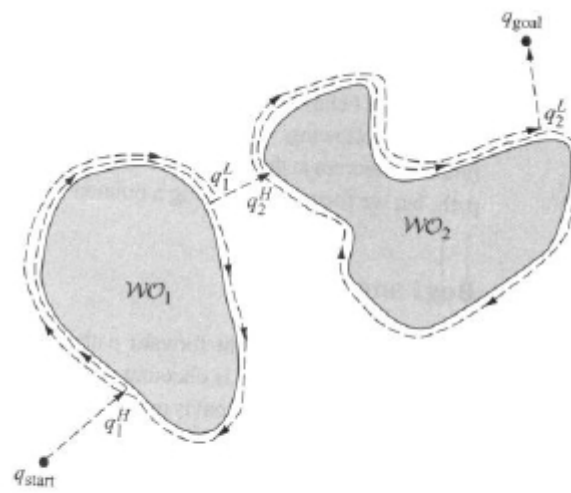# Bug1.

Figure 2.1 The Bug1 algorithm successfully finds the goal.

Bug2
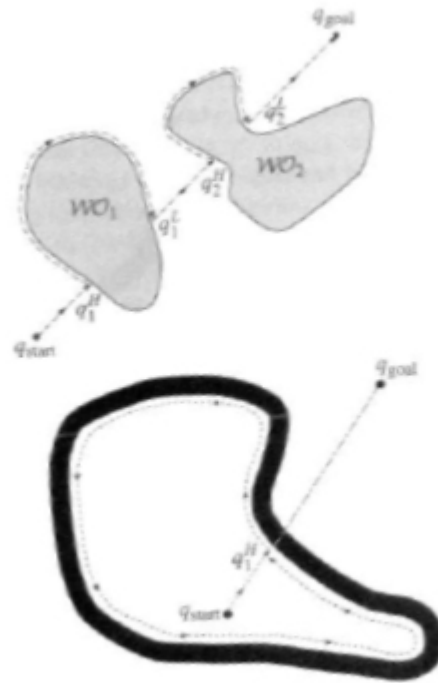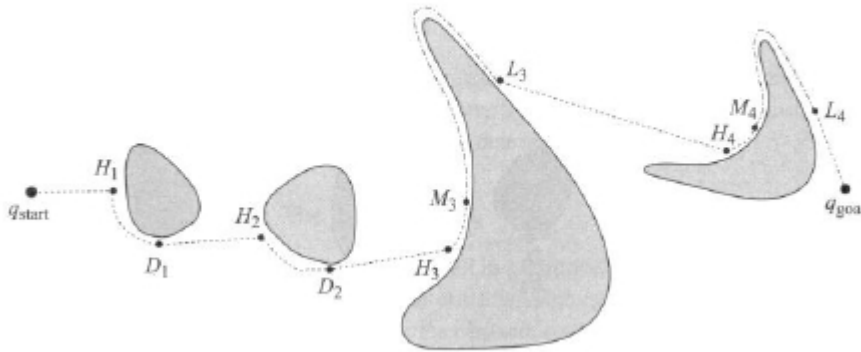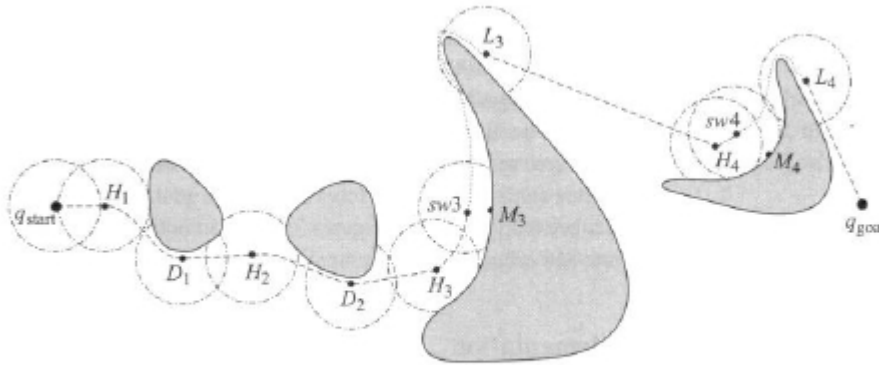
Figure 2.3 (Top) The Bug2 algorithm finds a path to the goal. (Bottom) The Bug2 algorithm reports failure.

Tangent Bug.

Figure 2.11 The path generated by Tangent Bug with zero sensor range. The dashed lines correspond to the motion-to-goal behavior and the dotted lines correspond to boundary-following.

Figure 2.12 Path generated by Tangent Bug with finite sensor range. The dashed lines correspond to the motion-to-goal behavior and the dotted lines correspond to boundary-following. The dashed-dotted circles correspond to the sensor range of the robot.