Chapter 1

Methodology

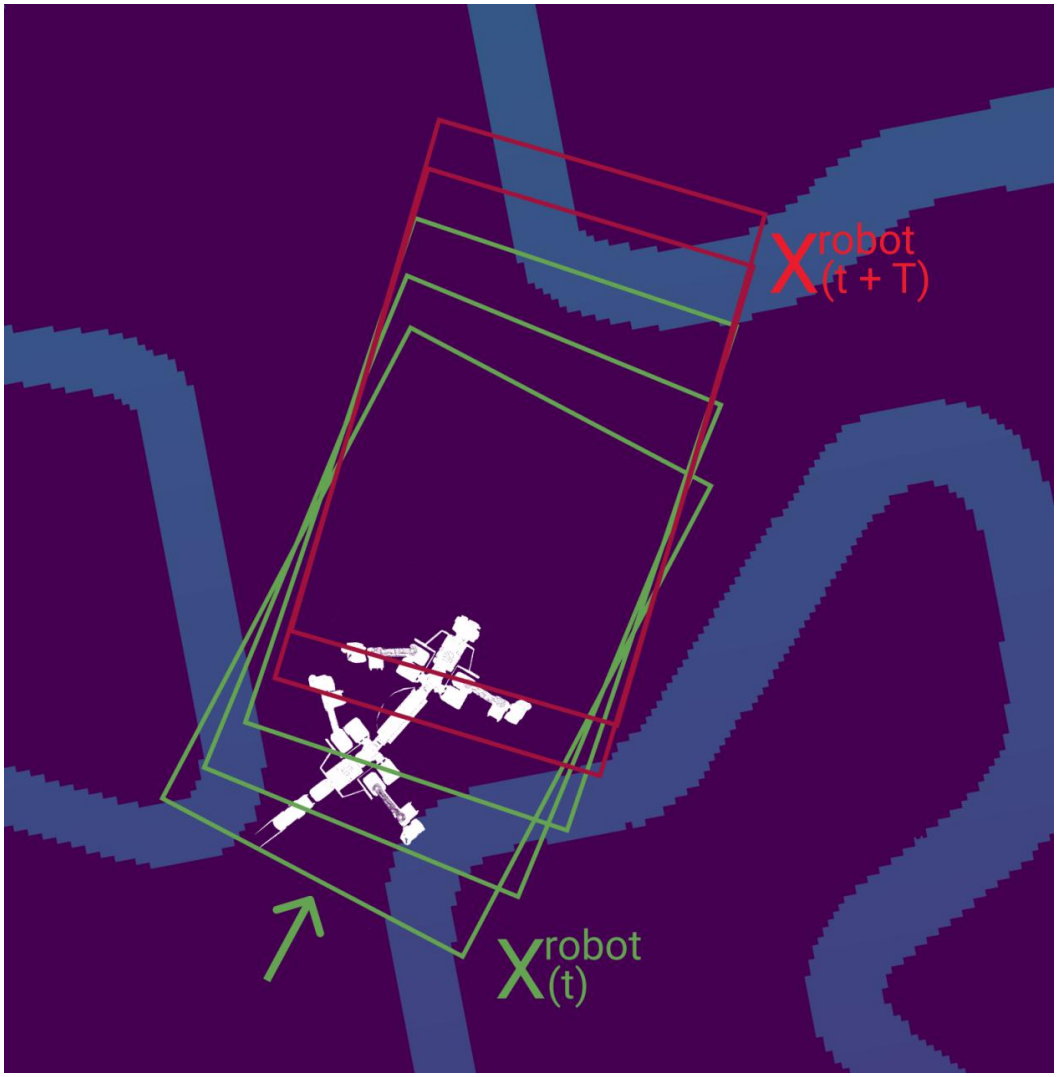

Figure 1.1. Example of a robot trajectory extracted during training from bars1. Robot's initial position is showed by its white siluette. Patches borders are label with greed if traversable and red if not.