Maze\_env.py

**new\_pose** = self.state + (action[0]) \* self.dt \* (

np.array([np.cos(action[1] \* np.pi), np.sin(action[1] \* np.pi)]))

🡪 straight lines, policy based on lines

Def **intersect** (19-46) and **collision** (220-223) [check if the new position collide with obstacles)

🡪 weak for concave shapes

**Step** (229-276)

🡪 incremental move, no considerations about the laby

Make\_maze (18-43)

🡪 obstacles only vertical-horizontal, no obliqui

Self.slide (248-259)

🡪 check only x,y pos, no obliqui