For instance, following problems are observed:

* The influence of obstacles to the final path has an effective range (it means that the path finding is not strictly global) this is due to that the equilibrium state of the neuronal state is not achievable in an acceptable time. The change in one step of the neuronal space will converge to a small value which will make the equilibrium state impossible to reach.
* The path found is not strictly the optimum path, the robot tends to keep a distance to any obstacles. This is also observed in the original paper only it was not mentioned.
* Sometimes the method could not find the path to a place hiding behind a big obstacle. This should not be the case as it is verified to be working in a labyrinth (Only in 2D case).

Things that we can do:

* Optimize
* Try other functions than and for g
* Study the conditions of convergence in high dimensions
* For project 2, it might be better if the x axis is fixed.