4/26/17

current issue:

1. Add the condition about the obj improvement to determine the trust region modification to see if any better result can happen. Current version does not work well.
   1. The resutls computed from cvx and from analytical computation are different. One possible reason is that in the objective function I removed a term that involves the determinant of covariance matrix.
2. A big bug: the sensor modeling method may not work when the sensing angle is greater than or equal to 180 (explain this in the paper to say we can always decompose into a disjoint set of convex shapes)
3. debug the whole program, think about using motion primitive for multiple initial guesses (e.g. moving towards MAP)

7/19/17

Nothing new since last note. Things to do:

1. follow CS287 method and add another condition for trust region change. make planning work
2. add code for FOV shape computation when obstacles exist. Use prob(occlusion) as gamma
3. add collision avoidance constraint
4. consider stochastic component (probability of occlusion, collision avoidance)