The Q-learning has been applied to many research projects in the past few decades. Its simple logic of given a state then find an action as well as its great performance has made it one of the most popular method in reinforcement learning. We are exploring the possible application of Q-learning in obstacle avoidance with a simple idea - the percept of the robot is taken as the state, and the actions gives instruction to the actuating device of the robot. Here a sanity check for such an idea was provided. Every component was as simple as possible. The most simple disc robot from Robotics Playground was used, and the most basic form of Q-learning is utilized. Our vehicle’s performance was checked in environments with different levels of environmental complexity. To monitor the process more easily, Simulink simulation was used to train the vehicle. Input from two distance sensors were used as the states and torque of two motors were provided as actions to construct the Q-learning table. Punishment was imposed when robot collided with the environment and no reward was given. The result showed very limited improvements in all of the environments and thus cast some doubt on the usability of this idea.