

# Project 1 Phase 3: A\* path finding and obstacle avoidance

状态	ELEC 5660
Lecture Note	<a href="#">proj1phase3_TONG_Zhe.zip</a>

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## Figures

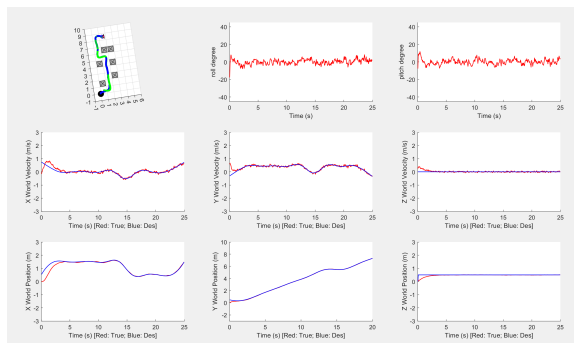


Fig. 1

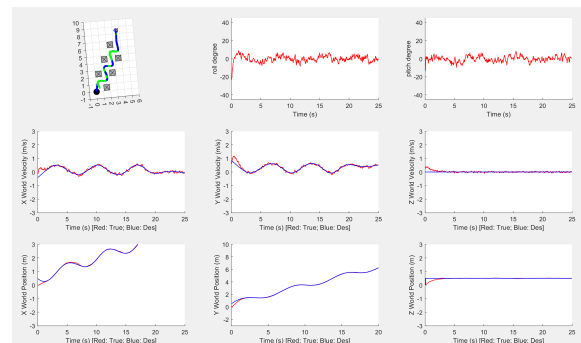


Fig.2

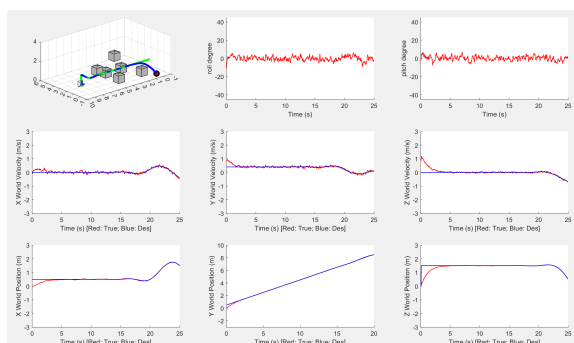


Fig.3

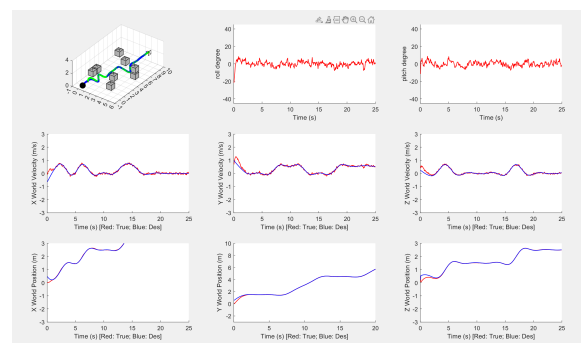


Fig.4

## 1. Path Visualization:

- **2D Maps:** (Fig. 1, Fig. 2) Drone flying in a 2D map where Z axis is ignored. The drone will have to fly in the same plane and cannot fly up to fly over all the obstacles.
  - **Random Maps:** (Fig. 3, Fig. 4). Drone can fly in any direction in 3D space.
2. **Trajectory Tracking:** Smooth trajectories generated by `trajectory_generator.m` at minimum snap