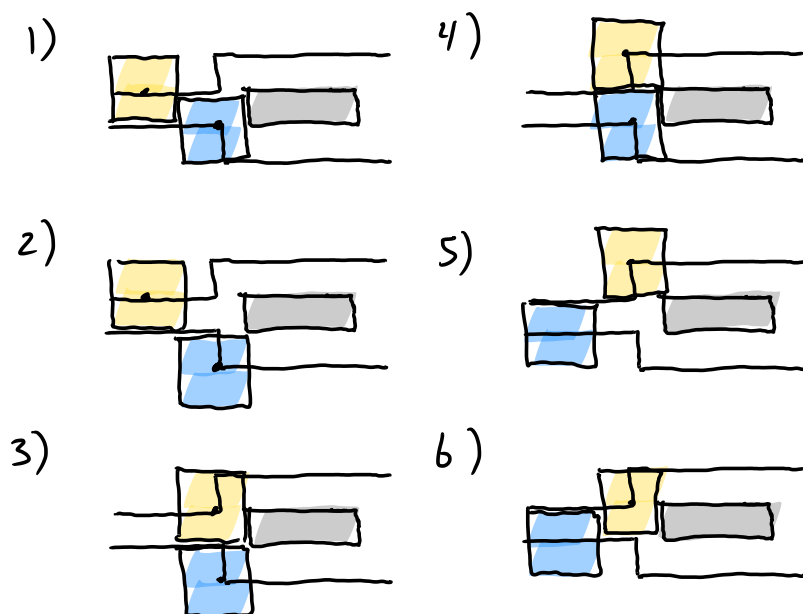
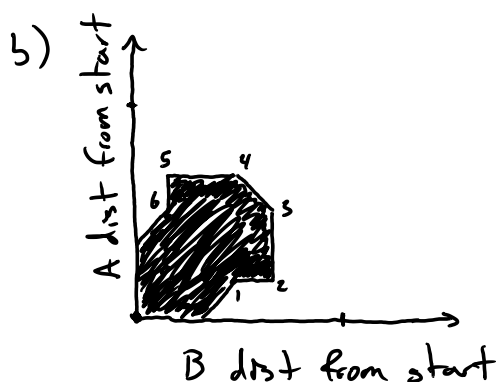


Ex 2

Tony Smoragiewicz

(0-a) a c-space could be drawn so that the x-axis is the distance Robot B has traveled and the y-axis is the distance that Robot A has traveled.



(7) Padding all obstacles made the path to the goal impossible. If we were able to change the main function I would use `meshgrid` and `interp2` to increase the cspace resolution before padding. This is much faster than increasing the resolution before computing the cspace.

M0) `check_collision`
This function is looking if points along each link are contained within any of the obstacles.

`check_edge`

This function calls the above function multiple times along a path. It only checks collisions at a set number of points along the line.

problems

- 1) This might be a graphics problem but the links that represent the revolute axes have a different radius than the links. The path can be "collision free" but still have these joints in collision
- 2) The functions don't include any swept hull capabilities so it's possible that a collision occurs between the resolution points.