

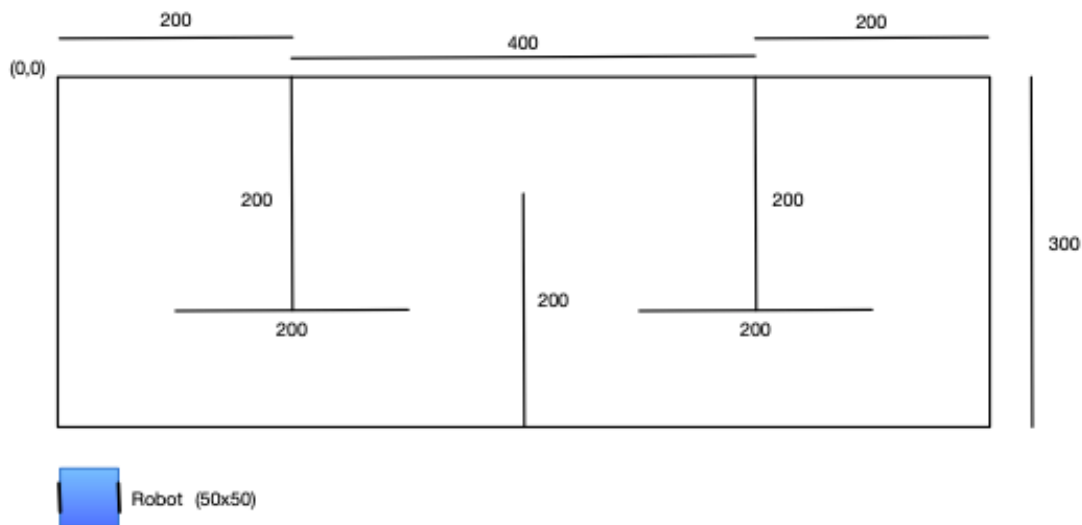
CSE_276C_Homework_5

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0.1 Homework 5 (Final) - CSE 276C - Math for Robotics

The world model is shown in figure 1. The robot is a differential drive system with a square geometry of size 50×50 .



0.1.1 Problem 1

Generate the configuration space for the robot with a grid size of 2×2 and 5 deg in angular resolution. Generate an illustration of what the configuration space looks like with the robot at orientations 0, 45 and 90 deg.

```
[35]: # Import necessary libraries
import math
import matplotlib.pyplot as plt
from matplotlib.patches import Rectangle
import matplotlib.cm as cm
%matplotlib inline
import numpy as np
import random
import skgeom as sg
```

```

from skgeom.draw import draw
from skgeom import minkowski
from skimage.draw import line_nd
from scipy.spatial import cKDTree

## Configuration
# Grid Resolution
grid_res = 2
angle_res = 5

# R2-D2 Robot Size
R2_D2_Robot_Size = np.array([50, 50])

# Starting point and end point from second part of the problem
strt_pt = np.array([50, 50])
end_pt = np.array([750, 50])

# Map Size
map_size_Width = (0, 800) # Width
map_size_Length = (0, 300) # Length

# Major Grid Size
major_grid_Width = np.arange(0, 801, 50)
major_grid_Length = np.arange(0, 301, 50)

# Minor Grid Size
minor_grid_Width = np.arange(0, 801, grid_res)
minor_grid_Length = np.arange(0, 301, grid_res)

# Thin and rigid walls (Robot Shall Not Pass! DANGER!)
# [[x-coords_line_1],[y-coords_line_1]],
# [[x-coords_line_2],[y-coords2_line_2]]
thin_walls = np.array([
    [[0, 0], [0, 300]],      # Outer left wall
    [[0, 800], [300, 300]],  # Outer bottom wall
    [[800, 800], [0, 300]],  # Outer right wall
    [[0, 800], [0, 0]],      # Outer top wall
    # Inner walls
    [[200, 200],[0, 200]],
    [[100, 300],[200, 200]],
    [[400, 400],[100, 300]],
    [[600, 600],[0, 200]],
    [[500, 700],[200, 200]],
])

### A.) Plot the Configuration Space
## 1.) Try plotting workspace first

```

```

# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
↪2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
↪2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
↪grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid
↪Wall", zorder = 1)
        continue

    plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

# g.) Plot the initial location of the robot
ax.add_patch(Rectangle((strt_pt[0]-R2_D2_Robot_Size[0]/2,
↪strt_pt[1]-R2_D2_Robot_Size[0]/2),
                        R2_D2_Robot_Size[0], R2_D2_Robot_Size[1],

```

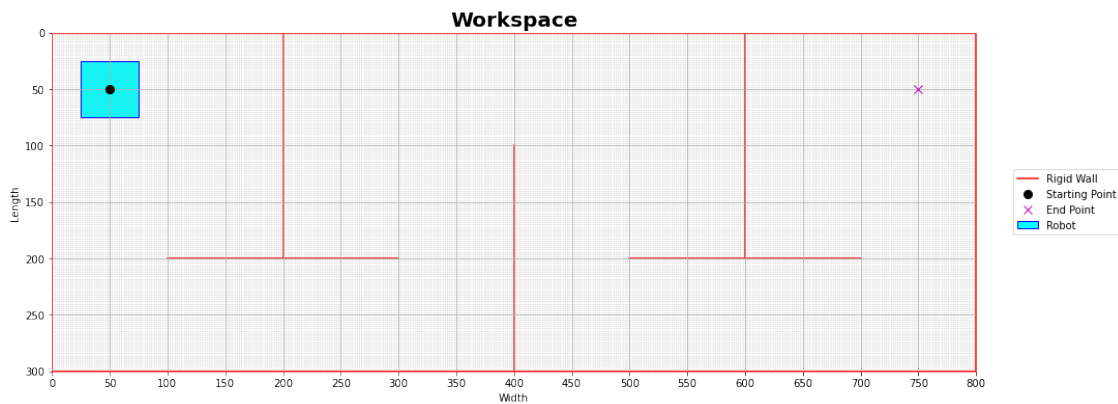
```

        edgecolor = 'blue',
        facecolor = 'cyan',
        fill = True,
        lw = 1,
        angle = 0,
        label = "Robot"))

# h.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'ko', label="Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label="End Point", markersize = 8)

# f.) Plot title
plt.title("Workspace", fontsize = 20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)
plt.show()

```



```

[36]: # Plot the configuration space with different orientation of the robots
robot_orientation = angle_res * round(0 / angle_res) # Degree

# Map Size
cspace_map_size_Width = (0, 800//grid_res) # Width
cspace_map_size_Length = (0, 300//grid_res) # Length

# Major Grid Size
cspace_major_grid_Width = np.arange(0, round(802/grid_res), 50)
cspace_major_grid_Length = np.arange(0, round(302/grid_res), 50)

# Minor Grid Size
cspace_minor_grid_Width = np.arange(0, round(802/grid_res), 1)
cspace_minor_grid_Length = np.arange(0, round(302/grid_res), 1)

## 1.) Plot configuration space with the robot orientation at 0 degree

```

```

# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(cspace_map_size_Width)
plt.ylim(cspace_map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(cspace_major_grid_Width)
ax.set_yticks(cspace_major_grid_Length)
plt.grid(visible = True, which='major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(cspace_minor_grid_Width, minor = True) # Set to 1 unit grid
ax.set_yticks(cspace_minor_grid_Length, minor = True) # Set to 1 unit grid
plt.grid(visible = True, which='minor', linestyle='-', alpha=0.2) # Minor grid
↳parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(np.round(thin_walls[idx][0]/grid_res), np.
↳round(thin_walls[idx][1]/grid_res), '-r', label = "Rigid Wall", zorder = 1)
        continue

        plt.plot(np.round(thin_walls[idx][0]/grid_res), np.round(thin_walls[idx][1]/
↳grid_res), '-r', zorder = 2)

# g.) Plot the initial location of the robot
ax.add_patch(Rectangle((round((100 - R2_D2_Robot_Size[0]/2)/grid_res),
↳round((100 - R2_D2_Robot_Size[1]/2)/grid_res)),
                    round(R2_D2_Robot_Size[0]/grid_res),
↳round(R2_D2_Robot_Size[1]/grid_res),

```

```

        edgecolor = 'blue',
        facecolor = 'cyan',
        fill = True,
        lw = 1,
        angle = robot_orientation,
        zorder = 2,
        label = "Robot"))

# h.) Plot the configuration space
for idx in range(0, thin_walls.shape[0]):

    # If the wall is a horizontal line
    if abs(thin_walls[idx][0][1] - thin_walls[idx][0][0]) > 0:

        # Label only once
        if idx == thin_walls.shape[0] - 1:

            ax.
            ↪add_patch(Rectangle((round((thin_walls[idx][0][0]-R2_D2_Robot_Size[0]/2)/
            ↪grid_res), round((thin_walls[idx][1][0]-R2_D2_Robot_Size[1]/2)/grid_res)),
                                round((abs(thin_walls[idx][0][1] -
            ↪thin_walls[idx][0][0]) + R2_D2_Robot_Size[0])/grid_res),
            ↪round(R2_D2_Robot_Size[1]/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                fill = True,
                                lw = 1,
                                angle = robot_orientation,
                                label = "Padding"))

        # Padding without labels
        else:

            ax.
            ↪add_patch(Rectangle((round((thin_walls[idx][0][0]-R2_D2_Robot_Size[0]/2)/
            ↪grid_res), round((thin_walls[idx][1][0]-R2_D2_Robot_Size[1]/2)/grid_res)),
                                round((abs(thin_walls[idx][0][1] -
            ↪thin_walls[idx][0][0]) + R2_D2_Robot_Size[0])/grid_res),
            ↪round(R2_D2_Robot_Size[1]/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                fill = True,
                                lw = 1,
                                angle = robot_orientation))

        # Vertical Wall
        else:

            # Label only once

```

```

        if idx == thin_walls.shape[0] - 1:

            ax.
            ↪add_patch(Rectangle((round((thin_walls[idx][0][0]-R2_D2_Robot_Size[0]/2)/
            ↪grid_res), round((thin_walls[idx][1][0]-R2_D2_Robot_Size[1]/2)/grid_res)),
                                round(R2_D2_Robot_Size[0]/grid_res),
            ↪round((abs(thin_walls[idx][1][1] - thin_walls[idx][1][0]) +
            ↪R2_D2_Robot_Size[1])/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                fill = True,
                                lw = 1,
                                angle = robot_orientation,
                                label = "Padding"))

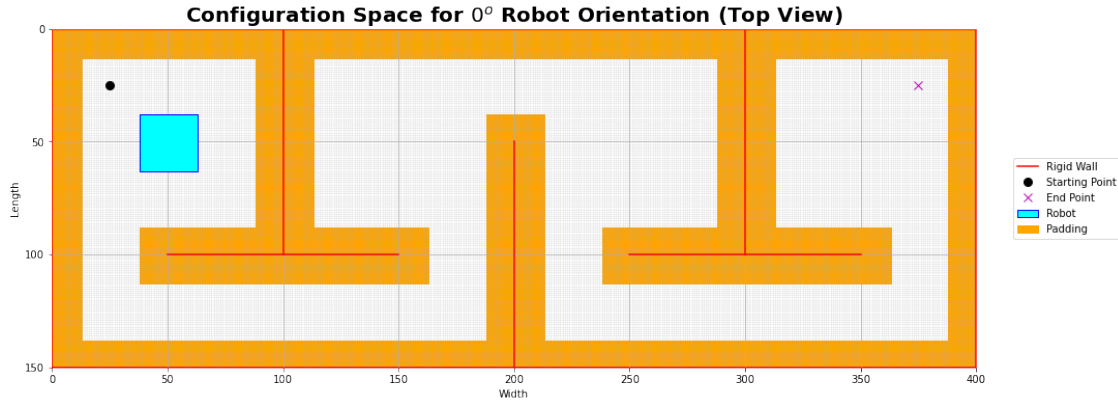
            # Padding without label
        else:

            ax.
            ↪add_patch(Rectangle((round((thin_walls[idx][0][0]-R2_D2_Robot_Size[0]/2)/
            ↪grid_res), round((thin_walls[idx][1][0]-R2_D2_Robot_Size[1]/2)/grid_res)),
                                round(R2_D2_Robot_Size[0]/grid_res),
            ↪round((abs(thin_walls[idx][1][1] - thin_walls[idx][1][0]) +
            ↪R2_D2_Robot_Size[1])/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                fill = True,
                                lw = 1,
                                angle = robot_orientation))

# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0]//grid_res, strt_pt[1]//grid_res, 'ko', label ="Starting
↪Point", markersize = 8)
plt.plot(end_pt[0]//grid_res, end_pt[1]//grid_res, 'mx', label ="End Point",
↪markersize = 8)

# j.) Plot title
plt.title("Configuration Space for $0^o$ Robot Orientation (Top View)",
↪fontsize = 20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)
plt.show()

```



```
[37]: # Plot the configuration space with different orientation of the robots
robot_orientation = angle_res * round(45 / angle_res) # 45 Degrees

## 1.) Plot configuration space with the robot orientation at 0 degree
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(cspace_map_size_Width)
plt.ylim(cspace_map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(cspace_major_grid_Width)
ax.set_yticks(cspace_major_grid_Length)
plt.grid(visible = True, which='major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(cspace_minor_grid_Width, minor = True) # Set to 1 unit grid
ax.set_yticks(cspace_minor_grid_Length, minor = True) # Set to 1 unit grid
plt.grid(visible = True, which='minor', linestyle='-', alpha=0.2) # Minor grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():
```



```

spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(np.round(thin_walls[idx][0]/grid_res), np.
→round(thin_walls[idx][1]/grid_res), '-r', label = "Rigid Wall", zorder = 1)
        continue

        plt.plot(np.round(thin_walls[idx][0]/grid_res), np.round(thin_walls[idx][1]/
→grid_res), '-r', zorder = 2)

# g.) Plot the initial location of the robot
ax.add_patch(Rectangle((round(100/grid_res), round((100 - np.
→sqrt(R2_D2_Robot_Size[0]**2 + R2_D2_Robot_Size[1]**2)/2)/grid_res)),
                    round(R2_D2_Robot_Size[0]/grid_res),
→round(R2_D2_Robot_Size[1]/grid_res),
                    edgecolor = 'blue',
                    facecolor = 'cyan',
                    fill = True,
                    lw = 1,
                    angle = robot_orientation,
                    zorder = 2,
                    label = "Robot"))

# h.) Plot the configuration space
for idx in range(0, thin_walls.shape[0]):

    # If the wall is a horizontal line
    if abs(thin_walls[idx][0][1] - thin_walls[idx][0][0]) > 0:

        # Label only once
        if idx == thin_walls.shape[0] - 1:

            ax.add_patch(Rectangle((round(thin_walls[idx][0][0]/grid_res),
→round((thin_walls[idx][1][0] - np.sqrt(R2_D2_Robot_Size[0]**2 +
→R2_D2_Robot_Size[1]**2)/2)/grid_res)),
                                round(R2_D2_Robot_Size[0]/grid_res),
→round(R2_D2_Robot_Size[1]/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                angle = robot_orientation,
                                fill = True,
                                lw = 1))

```

```

        ax.add_patch(Rectangle((round(thin_walls[idx][0][1]/grid_res),
↪round((thin_walls[idx][1][1] - np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2)/2)//grid_res)),
                                round(R2_D2_Robot_Size[0]/grid_res),
↪round(R2_D2_Robot_Size[1]/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                angle = robot_orientation,
                                fill = True,
                                lw = 1,
                                label = "Padding"))

        ax.add_patch(Rectangle((round(thin_walls[idx][0][0]/grid_res) ,
↪round((thin_walls[idx][1][0] - np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2)/2)/grid_res)),
                                round((abs(thin_walls[idx][0][1] -
↪thin_walls[idx][0][0]))/grid_res), round((np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2))/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                fill = True,
                                lw = 1))

        # Without label
        else:

            ax.add_patch(Rectangle((round(thin_walls[idx][0][0]/grid_res),
↪round((thin_walls[idx][1][0] - np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2)/2)/grid_res)),
                                    round(R2_D2_Robot_Size[0]/grid_res),
↪round(R2_D2_Robot_Size[1]/grid_res),
                                    edgecolor = 'orange',
                                    facecolor = 'orange',
                                    angle = robot_orientation,
                                    fill = True,
                                    lw = 1))

            ax.add_patch(Rectangle((round(thin_walls[idx][0][1]/grid_res),
↪round((thin_walls[idx][1][1] - np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2)/2)//grid_res)),
                                    round(R2_D2_Robot_Size[0]/grid_res),
↪round(R2_D2_Robot_Size[1]/grid_res),
                                    edgecolor = 'orange',
                                    facecolor = 'orange',
                                    angle = robot_orientation,

```

```

        fill = True,
        lw = 1))

    ax.add_patch(Rectangle((round(thin_walls[idx][0][0]/grid_res),
↪round((thin_walls[idx][1][0] - np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2)/2)/grid_res)),
                        round((abs(thin_walls[idx][0][1] -
↪thin_walls[idx][0][0]))/grid_res), round((np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2))/grid_res)),
                        edgecolor = 'orange',
                        facecolor = 'orange',
                        fill = True,
                        lw = 1))

    # Vertical Walls Padding
    else:

        ax.add_patch(Rectangle((round(thin_walls[idx][0][0]/grid_res),
↪round((thin_walls[idx][1][0] - np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2)/2)/grid_res)),
                        round(R2_D2_Robot_Size[0]/grid_res),
↪round(R2_D2_Robot_Size[1]/grid_res)),
                        edgecolor = 'orange',
                        facecolor = 'orange',
                        angle = robot_orientation,
                        fill = True,
                        lw = 1))

        ax.add_patch(Rectangle((round(thin_walls[idx][0][1]/grid_res),
↪round((thin_walls[idx][1][1] - np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2)/2)/grid_res)),
                        round(R2_D2_Robot_Size[0]/grid_res),
↪round(R2_D2_Robot_Size[1]/grid_res)),
                        edgecolor = 'orange',
                        facecolor = 'orange',
                        angle = robot_orientation,
                        fill = True,
                        lw = 1))

        ax.add_patch(Rectangle((round((thin_walls[idx][0][0] - np.
↪sqrt(R2_D2_Robot_Size[0]**2 + R2_D2_Robot_Size[1]**2)/2)/grid_res),
↪round(thin_walls[idx][1][0])/grid_res),
                        round((np.sqrt(R2_D2_Robot_Size[0]**2 +
↪R2_D2_Robot_Size[1]**2))/grid_res), round((abs(thin_walls[idx][1][1] -
↪thin_walls[idx][1][0]))/grid_res)),
                        edgecolor = 'orange',

```

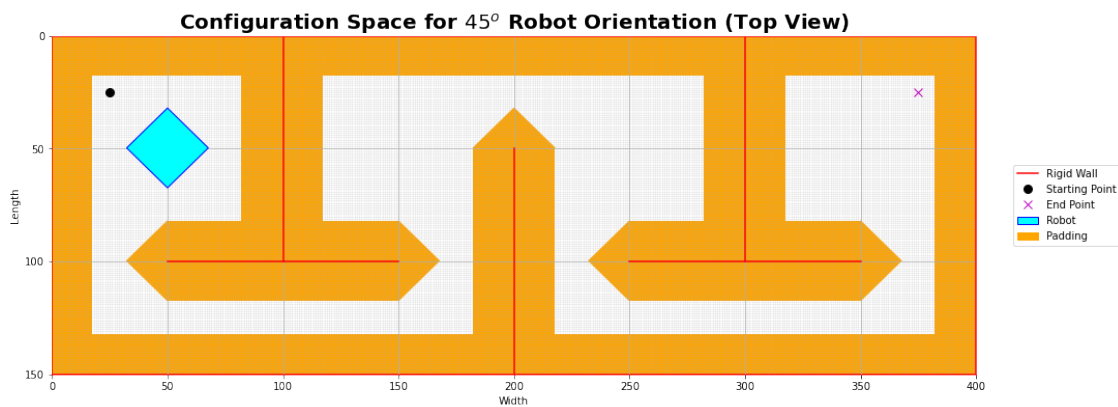
```

        facecolor = 'orange',
        fill = True,
        lw = 1))

# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0]//grid_res, strt_pt[1]//grid_res, 'ko', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0]//grid_res, end_pt[1]//grid_res, 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Configuration Space for 45° Robot Orientation (Top View)",
        fontsize = 20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)
plt.show()

```



```

[38]: # Plot the configuration space with different orientation of the robots
robot_orientation = angle_res * round(90 / angle_res) # 90 Degrees

## 1.) Plot configuration space with the robot orientation at 0 degree
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(cspace_map_size_Width)
plt.ylim(cspace_map_size_Length)
plt.gca().invert_yaxis()

```

```

# d.) Plot major grid
ax.set_xticks(cspace_major_grid_Width)
ax.set_yticks(cspace_major_grid_Length)
plt.grid(visible = True, which='major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(cspace_minor_grid_Width, minor = True) # Set to 1 unit grid
ax.set_yticks(cspace_minor_grid_Length, minor = True) # Set to 1 unit grid
plt.grid(visible = True, which='minor', linestyle='-', alpha=0.2) # Minor grid
↳ parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(np.round(thin_walls[idx][0]/grid_res), np.
↳ round(thin_walls[idx][1]/grid_res), '-r', label = "Rigid Wall", zorder = 1)
        continue

        plt.plot(np.round(thin_walls[idx][0]/grid_res), np.round(thin_walls[idx][1]/
↳ grid_res), '-r', zorder = 2)

# g.) Plot the initial location of the robot
ax.add_patch(Rectangle((round((100 + R2_D2_Robot_Size[0]/2)/grid_res),
↳ round((100 - R2_D2_Robot_Size[1]/2)/grid_res)),
                    round(R2_D2_Robot_Size[0]/grid_res),
↳ round(R2_D2_Robot_Size[1]/grid_res),
                    edgecolor = 'blue',
                    facecolor = 'cyan',
                    fill = True,
                    lw = 1,
                    angle = robot_orientation,
                    zorder = 2,
                    label = "Robot"))

# h.) Plot the configuration space
for idx in range(0, thin_walls.shape[0]):

    # If the wall is a horizontal line

```

```

if abs(thin_walls[idx][0][1] - thin_walls[idx][0][0]) > 0:

    # Label only once
    if idx == thin_walls.shape[0] - 1:

        ax.
        ↪add_patch(Rectangle((round((thin_walls[idx][0][0]-R2_D2_Robot_Size[0]/2)/
        ↪grid_res), round((thin_walls[idx][1][0]-R2_D2_Robot_Size[1]/2)/grid_res)),
                                round((abs(thin_walls[idx][0][1] -
        ↪thin_walls[idx][0][0]) + R2_D2_Robot_Size[0])/grid_res),
        ↪round(R2_D2_Robot_Size[1]/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                fill = True,
                                lw = 1,
                                label = "Padding"))

        # Padding without labels
    else:

        ax.
        ↪add_patch(Rectangle((round((thin_walls[idx][0][0]-R2_D2_Robot_Size[0]/2)/
        ↪grid_res), round((thin_walls[idx][1][0]-R2_D2_Robot_Size[1]/2)/grid_res)),
                                round((abs(thin_walls[idx][0][1] -
        ↪thin_walls[idx][0][0]) + R2_D2_Robot_Size[0])/grid_res),
        ↪round(R2_D2_Robot_Size[1]/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                fill = True,
                                lw = 1))

        # Vertical wall padding without labels
    else:

        ax.
        ↪add_patch(Rectangle((round((thin_walls[idx][0][0]-R2_D2_Robot_Size[0]/2)/
        ↪grid_res), round((thin_walls[idx][1][0]-R2_D2_Robot_Size[1]/2)/grid_res)),
                                round(R2_D2_Robot_Size[0]/grid_res),
        ↪round((abs(thin_walls[idx][1][1] - thin_walls[idx][1][0]) +
        ↪R2_D2_Robot_Size[1])/grid_res),
                                edgecolor = 'orange',
                                facecolor = 'orange',
                                fill = True,
                                lw = 1))

# i.) Plot the starting location and the ending location

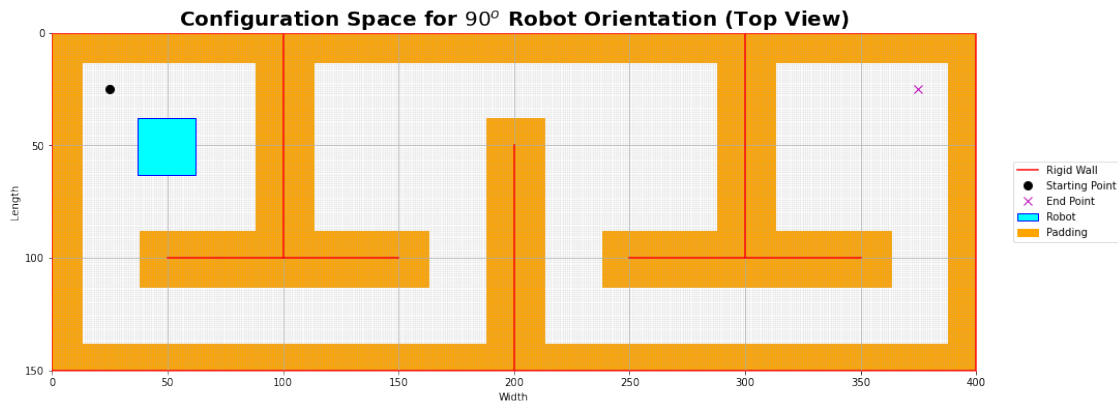
```

```

plt.plot(strt_pt[0]//grid_res, strt_pt[1]//grid_res, 'ko', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0]//grid_res, end_pt[1]//grid_res, 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Configuration Space for 90° Robot Orientation (Top View)",
          fontsize = 20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)
plt.show()

```



0.1.2 Problem 2

Use greedy search to find the shortest path between start-point (50,50) and end-point (750,50). Illustrate the path and provide its length.

```

[5]: ## Given:
# 1.) Grid resolution is 2, and angle resolution is 5
# 2.) Starting point (50, 50) and End-point (750, 50)

## Assumptions:
# 1.) Robot can only move to one of their 2 nearest neighbors (forward and backward) from its position.
# 2.) Robot could move up, and down with orientation 0 and 90 degrees.
# 3.) After the grid and cspace are transformed for robot orientation 45 degrees, robot could move diagonally forward and backward after it's rotated 45 degrees.
# 4.) The center point of the robot will be starting at the starting point.
# 5.) The edge of the robot will not intersect or overlap wall edges.

## Define the greedy algorithm, which is also known as Dijkstra Algorithm
      user-defined function

```

```

class Dijkstra_Algorithm:

    def __init__(self, obstacles, grid_res, angle_res, robot_Size = 1.0):

        # obstacles      : An array of obstacle nodes [[ox_1, oy_1], [ox_2,
        →oy_2], [ox_3, oy_3], ...]
        # robot_Size      : Maximum radius of the robot
        # grid_resolution : resolution of the grid in unit
        # angle_resolution: resolution of the grid in degree

        # Step 1: Initialization
        # Obstacles array
        self.obstacles = obstacles
        # Grid resolution
        self.grid_res = grid_res
        # Angle resolution
        self.angle_res = angle_res
        # Robot size
        self.robot_Size = robot_Size

        # Step 2: Data Extraction
        # Determine the lower and upper bounds of the configuration space
        self.min_Width = min(self.obstacles[:, 0])
        self.max_Width = max(self.obstacles[:, 0])
        self.min_Length = min(self.obstacles[:, 1])
        self.max_Length = max(self.obstacles[:, 1])

        # Create a unique ID for the dictionary
        def node_uniq_ID(self, node):

            # x_coord digit 1 , x_coord digit 2, x_coord digit 3, y_coord digit 1 ,
            →y_coord digit 2, y_coord digit 3
            uniq_ID = node.x * 1000 + node.y

            return uniq_ID

        def __call__(self, strt_pt, end_pt):

            # Create visited and unexplored dictionary.
            visited_nodes_set = {}
            unexplored_nodes_set = {}

            # Initial node
            init_Node = self.Node(strt_pt[0], strt_pt[1], 0, -1 )

            # Final node

```



```

final_Node = self.Node(end_pt[0], end_pt[1], 0, -1 )

# Iteration Count
iteration_count = 1

#Include the initial node to the unexplored set
unexplored_nodes_set[self.node_uniq_ID(init_Node)] = init_Node

# Start grid searching with while loop until the end point is found
while True:

    # Search the node with the lowest cost
    best_id = min(unexplored_nodes_set, key=lambda x:
↪unexplored_nodes_set[x].cost)

    # Best node
    best_node = unexplored_nodes_set[best_id]

    if iteration_count == 1:
        # Plot discovered nodes
        plt.plot(best_node.x, best_node.y, "*c", label = "Discovered_
↪Node")

    else:
        # Plot discovered nodes
        plt.plot(best_node.x, best_node.y, "*c")

    # Update iteration count
    iteration_count = iteration_count +1

    if best_node.x == final_Node.x and best_node.y == final_Node.y:

        # Final Node cost has the same previous index as the current_
↪best node previous index
        final_Node.prev_idx = best_node.prev_idx

        # Final Node cost is the current best node cost
        final_Node.cost = best_node.cost

        # End the while loop
        break

    # Include the best node to visited node set
    visited_nodes_set[best_id] = best_node

    # Remove the best node item from the unexplored node set/dictionary
    unexplored_nodes_set.pop(best_id)

```

```

        # Expanding directions to their nearest neighbour
        # [[x_magnitude, y_magnitude, euclidean_distance], [x_magnitude,
→y_magnitude, euclidean_distance],...]
        expand_directions = [[0, -grid_res, grid_res], # Move up
                             [0, grid_res, grid_res], # Move down
                             [-grid_res, 0, grid_res], # Move left
                             [grid_res, 0, grid_res], # Move right
                             [-grid_res, -grid_res, math.
→sqrt(2*(grid_res**2))], # Upper Left
                             [grid_res, -grid_res, math.
→sqrt(2*(grid_res**2))], # Upper Right
                             [-grid_res, grid_res, math.
→sqrt(2*(grid_res**2))], # Bottom Left
                             [grid_res, grid_res, math.
→sqrt(2*(grid_res**2))]] # Bottom Right

        # Expand search
        for neighbour_ID in range(0, len(expand_directions)):

            expanded_node = self.Node(best_node.x +
→expand_directions[neighbour_ID][0],
                                     best_node.y +
→expand_directions[neighbour_ID][1],
                                     best_node.cost +
→expand_directions[neighbour_ID][2],
                                     best_id)

            # Create an unique id for the node
            expanded_node_id = self.node_uniq_ID(expanded_node)

            # Check whether it is a visited node
            if expanded_node_id in visited_nodes_set:

                # Skip this loop
                continue

            # Check whether the node collide with any borders
            # Convert obstacles array to list
            obs_arr = self.obstacles
            obs_list = obs_arr.tolist()
            # Node to check
            node_check = np.array([expanded_node.x, expanded_node.y])
            # If the node is in the list
            if np.any(np.all(node_check == obs_list, axis=1)):

```

```

        # Skip this loop
        continue

    # If the node is not in the unvisited set but discovered
    if expanded_node_id not in unexplored_nodes_set:

        # Add to the unexplored set
        unexplored_nodes_set[expanded_node_id] = expanded_node

    else:

        # If discovered but the current one has lesser cost than
        → the previous
        if expanded_node.cost <=
        → unexplored_nodes_set[expanded_node_id].cost:

            # Replace it
            unexplored_nodes_set[expanded_node_id] = expanded_node

    # Determine the final path
    # Store best path from final node to start
    best_path = []

    # Add the final node to the best path
    best_path.append(np.array([final_Node.x, final_Node.y]))

    # Previous node of the final node
    previous_idx = final_Node.prev_idx

    # While not the starting node
    while previous_idx != -1:

        # Node from visited set
        node_visited = visited_nodes_set[previous_idx]
        best_path.append(np.array([node_visited.x, node_visited.y]))
        # Update the previous index
        previous_idx = node_visited.prev_idx

    # convert best_path from list to array
    best_path = np.array(best_path)

    return best_path

# Create subclass for nodes
class Node:

```

```

def __init__(self, x, y, cost, prev_index):

    # x-coordinate of the node
    self.x = x
    # y-coordinate of the node
    self.y = y
    # Cost of the node (distance moved + euclidean distance)
    self.cost = cost
    # Previous index to trace back where it came from
    self.prev_idx = prev_index

def __call__(self):

    # If the node is called, return an array of node information
    return np.array([self.x, self.y, self.cost, self.prev_idx])

# Calculate the maximum size of the robot
#robot_Size = np.sqrt(R2_D2_Robot_Size[0]**2 + R2_D2_Robot_Size[1]**2)/2
# Round to 2 grid resolutions
#robot_Size = grid_res * math.ceil(robot_Size/grid_res)
robot_Size = grid_res * math.ceil(R2_D2_Robot_Size[0]/2/grid_res)

# Define all the obstacle nodes
obstacles = []
obs_corns = [] # Store obstacle corners only

# Define the borders where the center point of the robot cannot pass.
# Bottom Left Horizontal Border
for idx in range(0 + robot_Size , 400 - robot_Size + grid_res, grid_res):

    obs_node = [idx, 300 - robot_Size]

    obstacles.append(obs_node)

# Bottom Right Horizontal Border
for idx in range(400 + robot_Size , 800 - robot_Size + grid_res, grid_res):

    obs_node = [idx, 300 - robot_Size]

    obstacles.append(obs_node)

# Center Left Upper Left Horizontal Border
for idx in range(100 - robot_Size , 200 - robot_Size + grid_res, grid_res):

    obs_node = [idx, 200 - robot_Size]

```

```

    obstacles.append(obs_node)

# Center Left Upper Right Horizontal Border
for idx in range(200 + robot_Size , 300 + robot_Size + grid_res, grid_res):

    obs_node = [idx, 200 - robot_Size]

    obstacles.append(obs_node)

# Center Right Upper Left Horizontal Border
for idx in range(500 - robot_Size , 600 - robot_Size + grid_res, grid_res):

    obs_node = [idx, 200 - robot_Size]

    obstacles.append(obs_node)

# Center Right Upper Right Horizontal Border
for idx in range(600 + robot_Size , 700 + robot_Size + grid_res, grid_res):

    obs_node = [idx, 200 - robot_Size]

    obstacles.append(obs_node)

# Center Left Bottom Horizontal Border
for idx in range(100 - robot_Size , 300 + robot_Size + grid_res, grid_res):

    obs_node = [idx, 200 + robot_Size]

    obstacles.append(obs_node)

# Center Right Bottom Horizontal Border
for idx in range(500 - robot_Size , 700 + robot_Size + grid_res, grid_res):

    obs_node = [idx, 200 + robot_Size]

    obstacles.append(obs_node)

# Top Left Horizontal Border
for idx in range(0 + robot_Size , 200 - robot_Size + grid_res, grid_res):

    obs_node = [idx, 0 + robot_Size]

    obstacles.append(obs_node)

# Top Center Horizontal Border
for idx in range(200 + robot_Size , 600 - robot_Size + grid_res, grid_res):

```

```

obs_node = [idx, 0 + robot_Size]

obstacles.append(obs_node)

# Top Right Horizontal Border
for idx in range(600 + robot_Size , 800 - robot_Size + grid_res, grid_res):

    obs_node = [idx, 0 + robot_Size]

    obstacles.append(obs_node)

# Center-Center Horizontal Border
for idx in range(400 - robot_Size , 400 + robot_Size + grid_res, grid_res):

    obs_node = [idx, 100 - robot_Size]

    obstacles.append(obs_node)

# Left Most Vertical Border
for idx in range(0 + robot_Size , 300 - robot_Size + grid_res, grid_res):

    obs_node = [0 + robot_Size, idx]

    obstacles.append(obs_node)

# 2nd Most Left Vertical Border
for idx in range(200 - robot_Size , 200 + robot_Size + grid_res, grid_res):

    obs_node = [100 - robot_Size, idx]

    obstacles.append(obs_node)

# 3rd Most Left Vertical Border
for idx in range(0 + robot_Size , 200 - robot_Size + grid_res, grid_res):

    obs_node = [200 - robot_Size, idx]

    obstacles.append(obs_node)

# 4th Most Left Vertical Border
for idx in range(0 + robot_Size , 200 - robot_Size + grid_res, grid_res):

    obs_node = [200 + robot_Size, idx]

    obstacles.append(obs_node)

# 5th Most Left Vertical Border

```

```

for idx in range(200 - robot_Size , 200 + robot_Size + grid_res, grid_res):

    obs_node = [300 + robot_Size, idx]

    obstacles.append(obs_node)

# Center Left Vertical Border
for idx in range(100 - robot_Size , 300 - robot_Size + grid_res, grid_res):

    obs_node = [400 - robot_Size, idx]

    obstacles.append(obs_node)

# Center Right Vertical Border
for idx in range(100 - robot_Size , 300 - robot_Size + grid_res, grid_res):

    obs_node = [400 + robot_Size, idx]

    obstacles.append(obs_node)

# Right Most Vertical Border
for idx in range(0 + robot_Size , 300 - robot_Size + grid_res, grid_res):

    obs_node = [800 - robot_Size, idx]

    obstacles.append(obs_node)

# 2nd Most Right Vertical Border
for idx in range(200 - robot_Size , 200 + robot_Size + grid_res, grid_res):

    obs_node = [700 + robot_Size, idx]

    obstacles.append(obs_node)

# 3rd Most Right Vertical Border
for idx in range(0 + robot_Size , 200 - robot_Size + grid_res, grid_res):

    obs_node = [600 + robot_Size, idx]

    obstacles.append(obs_node)

# 4th Most Right Vertical Border
for idx in range(0 + robot_Size , 200 - robot_Size + grid_res, grid_res):

    obs_node = [600 - robot_Size, idx]

    obstacles.append(obs_node)

```

```

# 5th Most Right Vertical Border
for idx in range(200 - robot_Size , 200 + robot_Size + grid_res, grid_res):

    obs_node = [500 - robot_Size, idx]

    obstacles.append(obs_node)

# Store all the corners of the border
obs_corns.append([0 + robot_Size, 0 + robot_Size])
obs_corns.append([0 + robot_Size, 300 - robot_Size])
obs_corns.append([400 - robot_Size, 300 - robot_Size])
obs_corns.append([400 - robot_Size, 100 - robot_Size])
obs_corns.append([400 + robot_Size, 100 - robot_Size])
obs_corns.append([400 + robot_Size, 300 - robot_Size])
obs_corns.append([800 - robot_Size, 300 - robot_Size])
obs_corns.append([800 - robot_Size, 0 + robot_Size])
obs_corns.append([600 + robot_Size, 0 + robot_Size])
obs_corns.append([600 + robot_Size, 200 - robot_Size])
obs_corns.append([700 + robot_Size, 200 - robot_Size])
obs_corns.append([700 + robot_Size, 200 + robot_Size])
obs_corns.append([500 - robot_Size, 200 + robot_Size])
obs_corns.append([500 - robot_Size, 200 - robot_Size])
obs_corns.append([600 - robot_Size, 200 - robot_Size])
obs_corns.append([600 - robot_Size, 0 + robot_Size])
obs_corns.append([200 + robot_Size, 0 + robot_Size])
obs_corns.append([200 + robot_Size, 200 - robot_Size])
obs_corns.append([300 + robot_Size, 200 - robot_Size])
obs_corns.append([300 + robot_Size, 200 + robot_Size])
obs_corns.append([100 - robot_Size, 200 + robot_Size])
obs_corns.append([100 - robot_Size, 200 - robot_Size])
obs_corns.append([200 - robot_Size, 200 - robot_Size])
obs_corns.append([200 - robot_Size, 0 + robot_Size])
obs_corns.append([0 + robot_Size, 0 + robot_Size])

# Convert list into an array
obs_corns = np.array(obs_corns)
obstacles = np.array(obstacles)

#print(obstacles.shape)

### A.) Plot the Configuration Space
## 1.) Try plotting workspace first
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis

```



```

plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
↪2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
↪2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
↪grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid
↪Wall", zorder = 1)
        continue

    plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

# plt.scatter(obstacles[:,0], obstacles[:,1], color = 'black', label = "Border
↪Corners")
plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center
↪Point of the Robot cannot Pass")

# h.) Run greedy algorithm
greedy_alg = Dijkstra_Algorithm(obstacles, grid_res, angle_res)

```

```

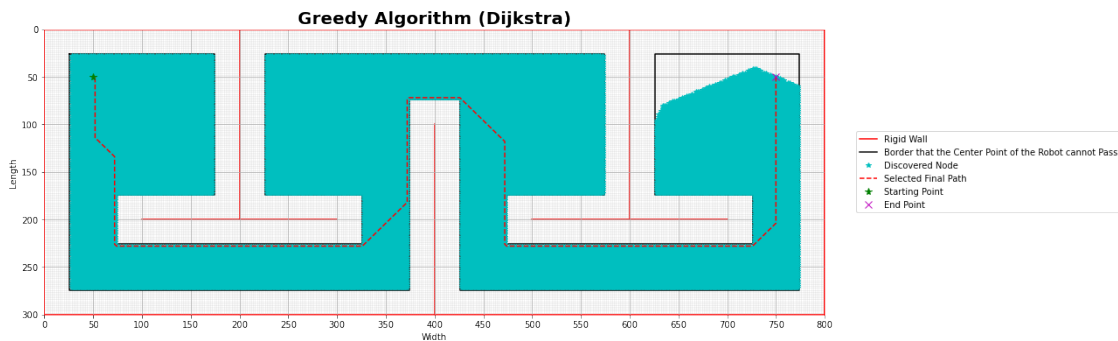
best_path = greedy_alg(strt_pt, end_pt)
plt.plot(best_path[:, 0], best_path[:, 1], "--r", label = 'Selected Final
↳Path') # Plot the final path

# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Greedy Algorithm (Dijkstra)", fontsize = 20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

# Show the final plot
plt.show()

```



```

[6]: # Calculate the total length of the path
greedy_path_length = 0

for idx in range(0, best_path.shape[0] - 1):

    # Euclidean Distance
    x_delta_sq = abs(best_path[idx, 0] - best_path[idx + 1, 0])**2
    y_delta_sq = abs(best_path[idx, 1] - best_path[idx + 1, 1])**2
    edge_length = math.sqrt(x_delta_sq + y_delta_sq)

    # Cumulated distance
    greedy_path_length = greedy_path_length + edge_length

print("Greedy Algorithm (Dijkstra) Path Length: ", greedy_path_length, " units")

```

Greedy Algorithm (Dijkstra) Path Length: 1283.6467529817269 units

0.1.3 Problem 3

Compute the safest path from start to finish (hint: medial axis transform/Voronoi). Illustrate the path and provide its length.

```
[7]: ## Voronoi Implementation:
# 1.) Create a cspace polygon with scikit-geometry.
# 2.) Generate Voronoi path with the cspace polygon using the scikit-geometry
→skeleton function
# 3.) Extract the vertices from the voronoi path.
# 4.) Eliminate the vertices and edges that collide with the obstacles
# 5.) Connect the starting point to its nearest vertex.
# 6.) Connect the ending point to its nearest vertex.
# 7.) With the vertices from Voronoi and the given final and starting points,
→determine the final path.

# Borders Polygon
border_Poly = sg.Polygon([sg.Point2(obs_corns[7,0], obs_corns[7,1]), sg.
→Point2(obs_corns[6,0], obs_corns[6,1]),
                        sg.Point2(obs_corns[5,0], obs_corns[5,1]), sg.
→Point2(obs_corns[4,0], obs_corns[4,1]),
                        sg.Point2(obs_corns[3,0], obs_corns[3,1]), sg.
→Point2(obs_corns[2,0], obs_corns[2,1]),
                        sg.Point2(obs_corns[1,0], obs_corns[1,1]), sg.
→Point2(obs_corns[0,0], obs_corns[0,1]),
                        sg.Point2(obs_corns[23,0], obs_corns[23,1]), sg.
→Point2(obs_corns[22,0], obs_corns[22,1]),
                        sg.Point2(obs_corns[21,0], obs_corns[21,1]), sg.
→Point2(obs_corns[20,0], obs_corns[20,1]),
                        sg.Point2(obs_corns[19,0], obs_corns[19,1]), sg.
→Point2(obs_corns[18,0], obs_corns[18,1]),
                        sg.Point2(obs_corns[17,0], obs_corns[17,1]), sg.
→Point2(obs_corns[16,0], obs_corns[16,1]),
                        sg.Point2(obs_corns[15,0], obs_corns[15,1]), sg.
→Point2(obs_corns[14,0], obs_corns[14,1]),
                        sg.Point2(obs_corns[13,0], obs_corns[13,1]), sg.
→Point2(obs_corns[12,0], obs_corns[12,1]),
                        sg.Point2(obs_corns[11,0], obs_corns[11,1]), sg.
→Point2(obs_corns[10,0], obs_corns[10,1]),
                        sg.Point2(obs_corns[9,0], obs_corns[9,1]), sg.
→Point2(obs_corns[8,0], obs_corns[8,1])])

class Voronoi_Algorithm:

    def __init__(self, obstacles, grid_res, border_Poly, angle_res, robot_Size,
→= 1.0):
```

```

        # obstacles      : An array of obstacle nodes [[ox_1, oy_1], [ox_2,
→oy_2], [ox_3, oy_3], ...]
        # border_Poly     : Polygon of the border
        # grid_resolution : resolution of the grid in unit
        # angle_resolution: resolution of the grid in degree
        # robot_Size      : Maximum radius of the robot

        # Step 1: Initialization
        # Obstacles array
        self.obstacles = obstacles
        # Grid resolution
        self.grid_res = grid_res
        # Angle resolution
        self.angle_res = angle_res
        # Robot size
        self.robot_Size = robot_Size
        # Polygon of the border
        self.polygon = border_Poly

        # Step 2: Data Extraction
        # Determine the lower and upper bounds of the configuration space
        self.min_Width = min(self.obstacles[:, 0])
        self.max_Width = max(self.obstacles[:, 0])
        self.min_Length = min(self.obstacles[:, 1])
        self.max_Length = max(self.obstacles[:, 1])

        # Create border skeleton from the its polygon
        self.border_skel = sg.skeleton.create_interior_straight_skeleton(self.
→polygon)

        # Create a list to store the vertices of the skeleton
        self.vertices_skel = []

        # Loop through all the vertices from the skeleton object
        for vertex in self.border_skel.vertices:

            # Store the vertices of the skeleton
            self.vertices_skel.append(np.array([vertex.point.x(), vertex.point.
→y()])))

        # Convert to array
        self.vertices_skel = np.array(self.vertices_skel)

    def __call__(self, strt_pt, end_pt):

```

```

# Convert obstacles array to list
obs_arr = self.obstacles
obs_list = obs_arr.tolist()

# Edge list that store skeleton edges
skel_edges = []

# Iteration counte
iteration = 1

# Plot the skeleton
for h in self.border_skel.halfedges:

    # Extract skeleton vertices
    v_1 = h.vertex.point
    v_2 = h.opposite.vertex.point
    v_1_pt = np.array([v_1.x(), v_1.y()])
    v_2_pt = np.array([v_2.x(), v_2.y()])

    # Label only once
    if iteration == 1:

        # Plot with label
        plt.plot([v_1.x(), v_2.x()], [v_1.y(), v_2.y()], 'b:', lw = 1,
→label = "Computed Voronoi Path")

    else:

        # Plot without label
        plt.plot([v_1.x(), v_2.x()], [v_1.y(), v_2.y()], 'b:', lw = 1)

    # Update iteration count
    iteration = iteration + 1

    # Ensure those vertices does not collide with the border
    if np.any(np.all(v_1_pt == obs_list, axis=1)):
        continue
    if np.any(np.all(v_2_pt == obs_list, axis=1)):
        continue

    # Only store the edges that does not touch the borders
    skel_edges.append(np.array([v_1.x(), v_1.y(), v_2.x(), v_2.y()]))

# Convert to array
skel_edges = np.array(skel_edges)

# Initialize starting edges that store vertices

```

```

start_edge = []
start_edge.append(strt_pt) # add starting point to the

# Set that store calculated euclidean distance
distances = []

# Find the nearest vertex from the starting point
for idx in range (0, self.vertices_skel.shape[0]):

    # Euclidean distance
    x_delta = self.vertices_skel[idx, 0] - strt_pt[0]
    y_delta = self.vertices_skel[idx, 1] - strt_pt[1]
    dist = math.sqrt(x_delta*x_delta + y_delta*y_delta)
    # Add to the list
    distances.append([dist, idx])

    # Sort the distances list from small to large
    distances.sort()

    # Choose the lowest 3
    distances = distances[:3]

# Determine which vertex to connect to from the starting point
for dist, idx in distances:

    # Node to check
    node_check = np.array([self.vertices_skel[idx, 0], self.
→vertices_skel[idx, 1]])

    # If the node is in the list
    if np.any(np.all(node_check == obs_list, axis=1)):

        # Skip this loop
        continue

    else:

        # Add to the start edge list
        start_edge.append(np.array([self.vertices_skel[idx, 0], self.
→vertices_skel[idx, 1]]))

        break

# Convert to array
start_edge = np.array(start_edge)

# Initialize ending edges that store vertices

```

```

end_edge = []

# Set that store calculated euclidean distance
distances = []

# Find the nearest vertex from the ending point
for idx in range (0, self.vertices_skel.shape[0]):

    # Euclidian distance
    x_delta = self.vertices_skel[idx, 0] - end_pt[0]
    y_delta = self.vertices_skel[idx, 1] - end_pt[1]
    dist = math.sqrt(x_delta*x_delta + y_delta*y_delta)
    # Add to the list
    distances.append([dist, idx])

    # Sort the distances list from small to large
    distances.sort()

    # Choose the lowest 3
    distances = distances[:3]

for dist, idx in distances:

    # Node to check
    node_check = np.array([self.vertices_skel[idx, 0], self.
↪vertices_skel[idx, 1]])

    # If the node is in the list
    if np.any(np.all(node_check == obs_list, axis=1)):

        # Skip this loop
        continue

    else:

        # Add to the end edge list
        end_edge.append(np.array([self.vertices_skel[idx, 0], self.
↪vertices_skel[idx, 1]]))

        break

# Add ending point to the
end_edge.append(end_pt)

# Convert to array
end_edge = np.array(end_edge)

```

```

# Flatten the start edge and end edge array
#start_edge = start_edge.flatten()
#end_edge = end_edge.flatten()

# Initialize the final path
route = []
# Add starting edge to the route list
route.append(start_edge[0])
route.append(start_edge[1])

# Initialize current node
curr_node = start_edge[1,:]
prev_node = start_edge[0,:]

# Arrange the sequence of the final path from start to finish
for iteration in range(0, skel_edges.shape[0]):

    for idx in range(0, skel_edges.shape[0]):

        # Skip duplicate edge
        if curr_node[0] == skel_edges[idx, 0] and curr_node[1] ==
↪skel_edges[idx, 1] and prev_node[0] == skel_edges[idx, 2] and prev_node[1]
↪== skel_edges[idx, 3]:

            continue

        # Find the next vertex
        if curr_node[0] == skel_edges[idx, 0] and curr_node[1] ==
↪skel_edges[idx, 1]:

            prev_node = curr_node
            curr_node = np.array([skel_edges[idx, 2], skel_edges[idx,
↪3]])

            route.append(curr_node)

        break

# Add starting edge to the route list
route.append(end_edge[0])
route.append(end_edge[1])

# Convert to array
route = np.array(route)

return route

```

```

### A.) Plot the Configuration Space

```



```

## 1.) Try plotting workspace first
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
↪2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
↪2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
↪grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid
↪Wall", zorder = 1)
        continue

    plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

#plt.scatter(obstacles[:,0], obstacles[:,1], color = 'black', label = "Border
↪Corners")

```

```

plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center_
↳Point of the Robot cannot Pass", lw = 3, zorder = 2)

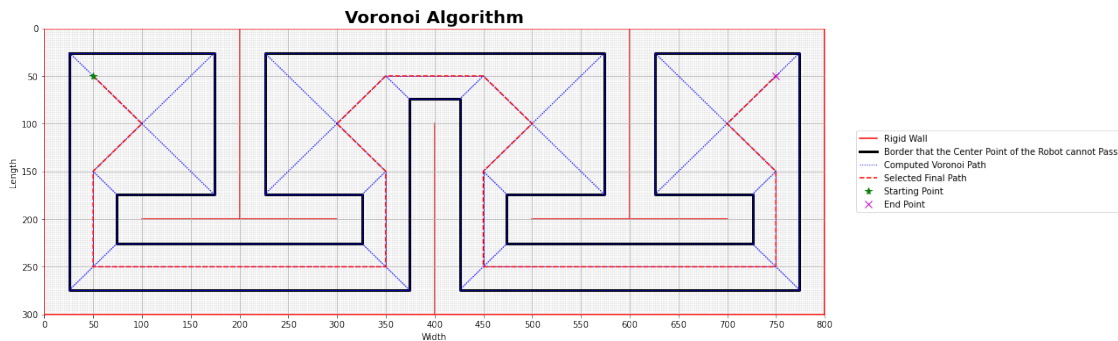
# h.) Run greedy algorithm
voronoi_alg = Voronoi_Algorithm(obstacles, grid_res, border_Poly, angle_res)
best_path = voronoi_alg(strt_pt, end_pt)
plt.plot(best_path[:, 0], best_path[:, 1], "--r", label = 'Selected Final_
↳Path') # Plot the final path

# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Voronoi Algorithm", fontsize = 20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

# Show the final plot
plt.show()

```



```

[8]: # Calculate the total length of the path
Voronoi_path_length = 0

for idx in range(0, best_path.shape[0] - 1):

    # Euclidean Distance
    x_delta = best_path[idx, 0] - best_path[idx + 1, 0]
    x_delta_sq = x_delta*x_delta
    y_delta = best_path[idx, 1] - best_path[idx + 1, 1]
    y_delta_sq = y_delta*y_delta
    edge_length = math.sqrt(x_delta_sq + y_delta_sq)

    # Cumulated distance
    Voronoi_path_length = Voronoi_path_length + edge_length

```

```
print("Voronoi Algorithm (Medical Axis) Path Length: ", Voronoi_path_length, "␣
↪units")
```

Voronoi Algorithm (Medical Axis) Path Length: 1665.685424949238 units

0.1.4 Problem 4

Use probabilistic roadmaps (PRM) to compute a path between start and end-points with 50, 100 and 500 sample points. What is the difference in path length? Illustrate each computed path.

a.) 50 samples

```
[21]: ## PRM Implementation:
# 1.) Uniformly and randomly sample the nodes inside the free space.
# 2.) For each node, connects to its k nearest neighbors (must not be the same␣
↪node and same edge) to create PRM edges.
# 3.) With given starting and ending points, connect them to the PRM roadmap.
# 4.) Determine the final path with greedy algorithm.
# 5.) Return empty set (if no final path), return final path if there is.

# Create obstacles list that store all the obstacle nodes
obs_list_PRM = []

### Draw the obstacles
## Outer Walls
# Top
for depth in range(0, robot_Size + grid_res, grid_res):

    for idx in range(0 , 800 + grid_res, grid_res):

        obs_node = [idx, depth]
        obs_list_PRM.append(obs_node)

# Right
for width in range(800, 800 - robot_Size - grid_res, -grid_res):

    for idx in range(0 , 300 + grid_res, grid_res):

        obs_node = [width, idx]
        obs_list_PRM.append(obs_node)

# Bottom
for depth in range(300, 300 - robot_Size - grid_res, -grid_res):

    for idx in range(800 , 0 - grid_res, -grid_res):

        obs_node = [idx, depth]
```

```

        obs_list_PRM.append(obs_node)

# Left
for width in range(0, robot_Size + grid_res, grid_res):

    for idx in range(300 , 0 - grid_res, -grid_res):

        obs_node = [width, idx]
        obs_list_PRM.append(obs_node)

## Inner Walls (Left to Right)
for width in range(200 - robot_Size, 200 + robot_Size + grid_res, grid_res):

    for idx in range(0 , 200 + grid_res, grid_res):

        obs_node = [width, idx]
        obs_list_PRM.append(obs_node)

for depth in range(200 - robot_Size, 200 + robot_Size + grid_res, grid_res):

    for idx in range(100 - robot_Size, 300 + robot_Size + grid_res, grid_res):

        obs_node = [idx, depth]
        obs_list_PRM.append(obs_node)

for width in range(400 - robot_Size, 400 + robot_Size + grid_res, grid_res):

    for idx in range(100 - robot_Size, 300 + grid_res, grid_res):

        obs_node = [width, idx]
        obs_list_PRM.append(obs_node)

for width in range(600 - robot_Size, 600 + robot_Size + grid_res, grid_res):

    for idx in range(0 , 200 + grid_res, grid_res):

        obs_node = [width, idx]
        obs_list_PRM.append(obs_node)

for depth in range(200 - robot_Size, 200 + robot_Size + grid_res, grid_res):
    for idx in range(500 - robot_Size, 700 + robot_Size + grid_res, grid_res):

        obs_node = [idx, depth]
        obs_list_PRM.append(obs_node)

# Convert to array
obs_array_PRM = np.array(obs_list_PRM)

```

```

class PRM_Algorithm():

    def __init__(self, obs_array_PRM, grid_res, angle_res, robot_Size, kNN,
→max_num_Samples):

        # obs_array_PRM : An array of obstacle nodes [[ox_1, oy_1], [ox_2,
→oy_2], [ox_3, oy_3], ...]
        # grid_resolution : resolution of the grid in unit
        # angle_resolution: resolution of the grid in degree
        # robot_Size : Maximum radius of the robot
        # kNN : k nearest neighbour
        # max_num_Samples : Maximum number of samples/iterations

        # Step 1: Initialization
        # Obstacles array
        self.obs_array_PRM = obs_array_PRM
        # Grid resolution
        self.grid_res = grid_res
        # Angle resolution
        self.angle_res = angle_res
        # Robot size
        self.robot_Size = robot_Size
        # Max number of neighbors
        self.kNN = kNN
        # Maximum iterations
        self.max_num_Samples = max_num_Samples

        # Step 2: Data Extraction
        # Determine the lower and upper bounds of the workspace
        self.min_x = min(self.obs_array_PRM[:, 0])
        self.max_x = max(self.obs_array_PRM[:, 0])
        self.min_y = min(self.obs_array_PRM[:, 1])
        self.max_y = max(self.obs_array_PRM[:, 1])

        # Create a unique ID for the PRM Graph dictionary
        def node_uniq_ID(self, PRM_node):

            # x_coord digit 1 , x_coord digit 2, x_coord digit 3, y_coord digit 1 ,
→y_coord digit 2, y_coord digit 3
            uniq_ID = PRM_node.x * 1000 + PRM_node.y

            return uniq_ID

        # Euclidean distance
        def euclidean_dist(self, n1_x, n1_y, n2_x, n2_y):

```

```

        return math.sqrt(abs(n1_x - n2_x)**2 + abs(n1_y - n2_y)**2)

# Call function
def __call__(self, strt_pt, end_pt):

    # Create a PRM Graph dictionary
    PRM_Graph = {}

    # Initial node
    init_Node = self.PRM_node(strt_pt[0], strt_pt[1], 0, -1 )

    # Final node
    final_Node = self.PRM_node(end_pt[0], end_pt[1], 0, -1 )

    # Initialize PRM nodes list [[x1, y1],[x2, y2],...]
    PRM_nodes_list = []

    # Initialize PRM sample count
    PRM_sample_count = 1

    # Start the iteration
    while PRM_sample_count <= self.max_num_Samples:

        # Get a random node x-coordinate
        nd_rand_x = random.randrange(self.min_x, self.max_x, grid_res)
        # Get a random node y-coordinate
        nd_rand_y = random.randrange(self.min_y, self.max_y, grid_res)
        # Random node
        nd_rand = np.array([nd_rand_x, nd_rand_y])
        rand_Node = self.PRM_node(nd_rand_x, nd_rand_y, 0, -1)
        nd_rand_ID = self.node_uniq_ID(rand_Node)

        # If the node is the same as initial node
        if nd_rand_ID == self.node_uniq_ID(init_Node):

            # Skip this loop
            continue

        # If the node is the same as final node
        if nd_rand_ID == self.node_uniq_ID(final_Node):

            # Skip this loop
            continue

        # Check whether the node is in the PRM Graph dictionary
        if nd_rand_ID in PRM_Graph:

```

```

        # Skip this loop
        continue

    # Check for collision
    if np.any(np.all(nd_rand == obs_list_PRM, axis=1)):

        # Skip this loop
        continue

    # Include the node to the PRM graph
    PRM_nodes_list.append(nd_rand)
    if PRM_sample_count == 1:

        # Label once
        plt.plot(nd_rand_x, nd_rand_y, "ob", label = "Randomly Sampled_
→Nodes")

    else:

        plt.plot(nd_rand_x, nd_rand_y, "ob")

    # Update the count
    PRM_sample_count = PRM_sample_count + 1

    # Include the initial and final nodes to the PRM node list
    PRM_nodes_list.append(strt_pt)
    PRM_nodes_list.append(end_pt)

    # Convert the PRM nodes list to array
    PRM_nodes_array = np.array(PRM_nodes_list)

    ## Generate PRM edges
    # Initialize the list that stores all the edges information
    PRM_edges_list = []
    # Number of Combination between Vertices (from nearest to furthest)
    vertices_Comb = cKDTree(PRM_nodes_array)

    iteration_label = 1

    for idx, [x_coord, y_coord] in enumerate(PRM_nodes_array):

        # Extract the distances and indices information from each node
        euclid_distances, indices = vertices_Comb.query([x_coord, y_coord],
→k = PRM_nodes_array.shape[0])

        # Create a list that stores information that the nodes connects to_
→which other nodes

```

```

edges_idx_list = []

# Start from 1 because the index 0 is the same coordinate
for idx_2 in range(1, PRM_nodes_array.shape[0]):

    # Find the neighbor node from the PRM nodes array
    neighbor_node = PRM_nodes_array[indices[idx_2],:]

    # Generate Nodes along the edge
    edge_nodes = line_nd((x_coord, y_coord), (neighbor_node[0],
↪neighbor_node[1]), endpoint=True)
    # Convert to array
    edge_nodes = np.array(edge_nodes)
    # Reshape it to number of nodes x 2
    edge_nodes = edge_nodes.T
    # Round up to grid resolution
    edge_nodes = grid_res * np.round(edge_nodes/grid_res)

    # Check for possible collision
    # Initialize collision status
    collision_status = False

    # Check each and every nodes along the edge
    for idx in range(0, edge_nodes.shape[0]):

        # If collision detected
        if np.any(np.all(edge_nodes[idx, :] == obs_list_PRM,
↪axis=1))):

            # Update collision status
            collision_status = True

            # Break the second for loop
            break

    # If no collision
    if collision_status == False:

        # Store neighbor node index for this node
        edges_idx_list.append(indices[idx_2])

        # Label once
        if iteration_label == 1 :

            # Plot the edges
            plt.plot([x_coord, neighbor_node[0]], [y_coord,
↪neighbor_node[1]], ":c", label = "PRM Generated Path")

```



```

        iteration_label = iteration_label + 1

    else:

        # Plot the edges
        plt.plot([x_coord, neighbor_node[0]], [y_coord,
↪neighbor_node[1]], ":c")

        # Store maximum number of neighbours if possible
        if len(edges_idx_list) >= self.kNN:

            # Stop the second for loop
            break

        # Add to the PRM edges list
        PRM_edges_list.append(edges_idx_list)

↪
# Greedy Algorithm on PRM
↪
# Create visited and unexplored dictionary.
visited_nodes_set = {}
unexplored_nodes_set = {}

# Initial node
init_Node = self.PRM_node(strt_pt[0], strt_pt[1], 0, -1 )

# Final node
final_Node = self.PRM_node(end_pt[0], end_pt[1], 0, -1 )

# Iteration Count
iteration_count = 1

# Include the initial node to the unexplored set
unexplored_nodes_set[len(PRM_edges_list) -2] = init_Node

# Initialize complete path status
complete_path_status = True

# Start grid searching with while loop until the end point is found
while True:

```

```

# If path is incomplete / all sub-group nodes are explored
if not unexplored_nodes_set:

    # Update path status
    complete_path_status = False

    # Print status
    print("Final node cannot be reached from the starting node.␣
↪Please adjust the number of samples.")

    break

# Search the node with the lowest cost
best_id = min(unexplored_nodes_set, key=lambda x:␣
↪unexplored_nodes_set[x].cost)

# Best node
best_node = unexplored_nodes_set[best_id]

if iteration_count == 1:
    # Plot discovered nodes
    plt.plot(best_node.x, best_node.y, "*c", label = "Discovered␣
↪Node")

else:
    # Plot discovered nodes
    plt.plot(best_node.x, best_node.y, "*c")

# Update iteration count
iteration_count = iteration_count +1

# If it is the final node
if best_id == (len(PRM_edges_list) -1):

    # Final Node cost has the same previous index as the current␣
↪best node previous index
    final_Node.parent_node_id = best_node.parent_node_id

    # Final Node cost is the current best node cost
    final_Node.cost = best_node.cost

    # End the while loop
    break

# Include the best node to visited node set
visited_nodes_set[best_id] = best_node

```

```

# Remove the best node item from the unexplored node set/dictionary
unexplored_nodes_set.pop(best_id)

# Search the connected vertices
for neighbour_ID in range(0, len(PRM_edges_list[best_id])):

    # Expanded node index
    expanded_node_idx = PRM_edges_list[best_id][neighbour_ID]

    # Calculate euclidean distance
    euclid_dist = self.
    ↪euclidean_dist(PRM_nodes_array[expanded_node_idx, 0],
    ↪PRM_nodes_array[expanded_node_idx, 1], best_node.x, best_node.y)

    # Define the expanded node
    expanded_node = self.
    ↪PRM_node(PRM_nodes_array[expanded_node_idx, 0],
    ↪PRM_nodes_array[expanded_node_idx, 1],
    ↪best_node.cost + euclid_dist,
    ↪best_id)

    # Check whether it is a visited node
    if expanded_node_idx in visited_nodes_set:

        # Skip this loop
        continue

    # If the node is not in the unvisited set but discovered
    if expanded_node_idx not in unexplored_nodes_set:

        # Add to the unexplored set
        unexplored_nodes_set[expanded_node_idx] = expanded_node

    else:

        # If discovered but the current one has lesser cost than
        ↪the previous
        if expanded_node.cost <
        ↪unexplored_nodes_set[expanded_node_idx].cost:

            # Update the cost and parent node index
            unexplored_nodes_set[expanded_node_idx].cost =
            ↪expanded_node.cost
            unexplored_nodes_set[expanded_node_idx].parent_node_id
            ↪= expanded_node.parent_node_id

```

```

if complete_path_status == False:

    # Empty path
    final_path = [[], []]
    final_path = np.array(final_path) # Convert to array

    return final_path

# Determine the final path
# Store best path from final node to start
final_path = []

# Add the final node to the best path
final_path.append(np.array([final_Node.x, final_Node.y]))

# Previous node of the final node
previous_idx = final_Node.parent_node_id

# While not the starting node
while previous_idx != -1:

    # Node from visited set
    node_visited = visited_nodes_set[previous_idx]
    final_path.append(np.array([node_visited.x, node_visited.y]))
    # Update the previous index
    previous_idx = node_visited.parent_node_id

# convert best_path from list to array
final_path = np.array(final_path)

# Print status
print("Congratulations! A complete path is found.")

return final_path

# Create subclass for PRM nodes
class PRM_node:

    def __init__(self, x, y, cost, parent_node_id):

        # x-coordinate of the node
        self.x = x
        # y-coordinate of the node
        self.y = y
        # cost (Distance travelled)
        self.cost = cost

```

```

        # Node parent key
        self.parent_node_id = parent_node_id

    def __call__(self):

        # If the node is called, return an array of node information
        return np.array([self.x, self.y, self.cost, self.parent_node_id])

### A.) Plot the Configuration Space
## 1.) Try plotting workspace first
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
→2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
→2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
→grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

```

```

plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid_
↳Wall", zorder = 1)
    continue

plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

#plt.scatter(obs_array_RRT[:,0], obs_array_RRT[:,1], color = 'black', label =_
↳"Walls")
plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center_
↳Point of the Robot cannot Pass")

# h.) Run PRM algorithm
prm_alg = PRM_Algorithm(obs_array_PRM, grid_res, angle_res, robot_Size, kNN =_
↳10, max_num_Samples = 50)
best_path = prm_alg(strt_pt, end_pt)
# If not empty path
if best_path.shape[1] != 0:
    # Plot the path
    plt.plot(best_path[:, 0], best_path[:, 1], "--r", lw = 3, label = 'Selected_
↳Final Path') # Plot the final path

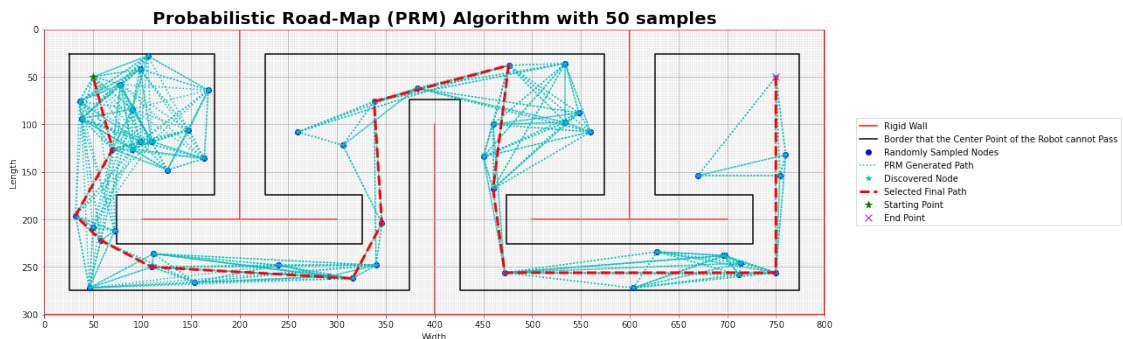
# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Probabilistic Road-Map (PRM) Algorithm with 50 samples", fontsize =_
↳20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

# Show the final plot
plt.show()

```

Congratulations! A complete path is found.



```
[22]: # Calculate the total length of the PRM path
PRM_path_length = 0

for idx in range(0, best_path.shape[0] - 1):

    # Euclidean Distance
    x_delta = best_path[idx, 0] - best_path[idx + 1, 0]
    x_delta_sq = x_delta*x_delta
    y_delta = best_path[idx, 1] - best_path[idx + 1, 1]
    y_delta_sq = y_delta*y_delta
    edge_length = math.sqrt(x_delta_sq + y_delta_sq)

    # Cumulated distance
    PRM_path_length = PRM_path_length + edge_length

print("PRM Algorithm Path Length with 50 samples: ", PRM_path_length, " units")
```

PRM Algorithm Path Length with 50 samples: 1500.8955190162997 units

b.) 100 samples

```
[23]: ### A.) Plot the Configuration Space
## 1.) Try plotting workspace first
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 xu
↪2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 xu
↪2
```

```

plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
    ↳grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid
    ↳Wall", zorder = 1)
        continue

    plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

#plt.scatter(obs_array_RRT[:,0], obs_array_RRT[:,1], color = 'black', label =
    ↳"Walls")
plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center
    ↳Point of the Robot cannot Pass")

# h.) Run PRM algorithm
prm_alg = PRM_Algorithm(obs_array_PRM, grid_res, angle_res, robot_Size, kNN =
    ↳10, max_num_Samples = 100)
best_path = prm_alg(strt_pt, end_pt)
# If not empty path
if best_path.shape[1] != 0:
    # Plot the path
    plt.plot(best_path[:, 0], best_path[:, 1], "--r", lw = 3, label = 'Selected
    ↳Final Path') # Plot the final path

# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Probabilistic Road-Map (PRM) Algorithm with 100 samples", fontsize =
    ↳20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

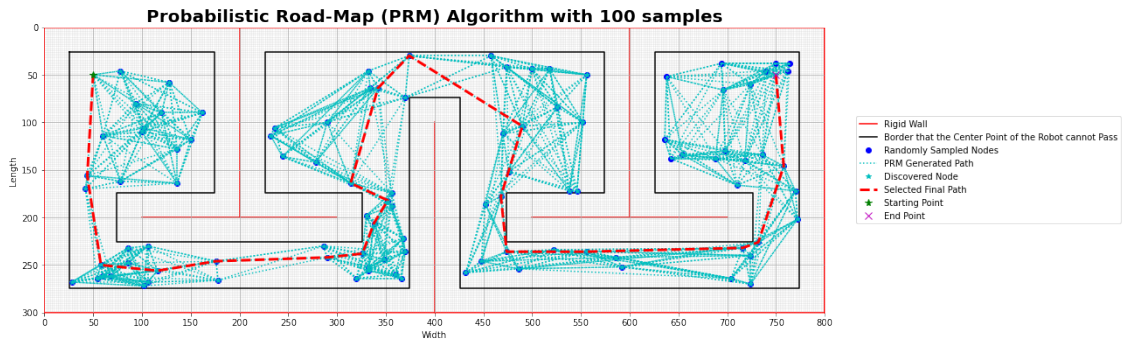
# Show the final plot

```



```
plt.show()
```

Congratulations! A complete path is found.



```
[24]: # Calculate the total length of the PRM path
PRM_path_length = 0

for idx in range(0, best_path.shape[0] - 1):

    # Euclidean Distance
    x_delta = best_path[idx, 0] - best_path[idx + 1, 0]
    x_delta_sq = x_delta*x_delta
    y_delta = best_path[idx, 1] - best_path[idx + 1, 1]
    y_delta_sq = y_delta*y_delta
    edge_length = math.sqrt(x_delta_sq + y_delta_sq)

    # Cumulated distance
    PRM_path_length = PRM_path_length + edge_length

print("PRM Algorithm Path Length with 100 samples: ", PRM_path_length, " units")
```

PRM Algorithm Path Length with 100 samples: 1437.8742335935567 units

c.) 150 samples

```
[17]: ### A.) Plot the Configuration Space
## 1.) Try plotting workspace first
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
```

```

plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
↪2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
↪2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
↪grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid
↪Wall", zorder = 1)
        continue

    plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

#plt.scatter(obs_array_RRT[:,0], obs_array_RRT[:,1], color = 'black', label =
↪"Walls")
plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center
↪Point of the Robot cannot Pass")

# h.) Run PRM algorithm
prm_alg = PRM_Algorithm(obs_array_PRM, grid_res, angle_res, robot_Size, kNN =
↪10, max_num_Samples = 150)
best_path = prm_alg(strt_pt, end_pt)
# If not empty path
if best_path.shape[1] != 0:
    # Plot the path

```

```

plt.plot(best_path[:, 0], best_path[:, 1], "--r", lw = 3, label = 'Selected_
↪Final Path') # Plot the final path

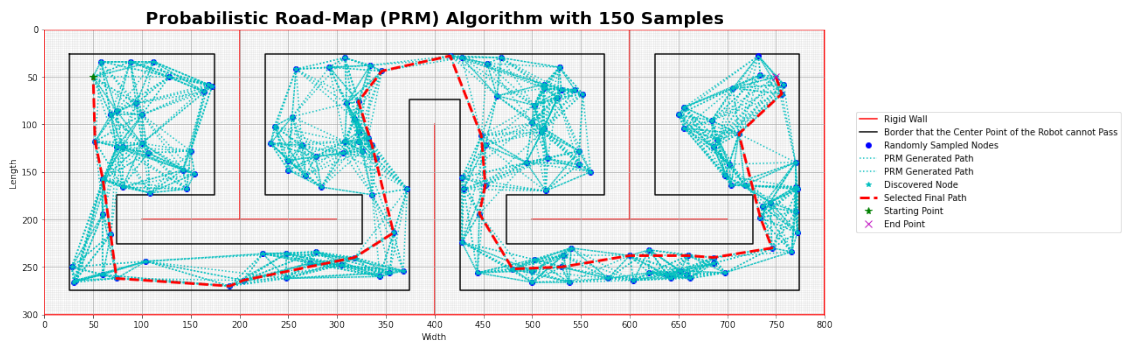
# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Probabilistic Road-Map (PRM) Algorithm with 150 Samples", fontsize = ↪
↪20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

# Show the final plot
plt.show()

```

Congratulations! A complete path is found.



```

[18]: # Calculate the total length of the PRM path
PRM_path_length = 0

for idx in range(0, best_path.shape[0] - 1):

    # Euclidean Distance
    x_delta = best_path[idx, 0] - best_path[idx + 1, 0]
    x_delta_sq = x_delta*x_delta
    y_delta = best_path[idx, 1] - best_path[idx + 1, 1]
    y_delta_sq = y_delta*y_delta
    edge_length = math.sqrt(x_delta_sq + y_delta_sq)

    # Cumulated distance
    PRM_path_length = PRM_path_length + edge_length

print("PRM Algorithm Path Length with 150 samples: ", PRM_path_length, " units")

```

PRM Algorithm Path Length with 150 samples: 1476.4748865381866 units

Comments on the difference in path length of 50, 100, and 150 samples: As the number of the samples increases, the higher the density of the generated probabilistic roadmaps (PRM) nodes. The length of the edges that connect the 2 vertices are shorter due to higher density of the generated probabilistic roadmaps (PRM) nodes. As a results, increasing the number of samples creates a more refined path, which decreases the length of the final path. Besides that, if the number of samples is too low or insufficient, it might not generate a final path due to the low density of the PRM nodes; some vertices are unable to connect to their nearest k (i.e., 10 for all different samples) neighbours due to obstacle in their way.

0.1.5 Problem 5

Do the same with Rapid exploring random trees (RRT). What are the main differences in performance between PRM and RRT? Illustrate each path.

a.) 50 samples

```
[47]: ## RRT Implementation:
# 1.) Initialize RRT graph.
# 2.) Loop through the while loop until final goal is reached or maximum
↳ iterations are reached.
# a.) Generate a random point
# b.) Check for collision and RRT Graph whether there is collision or same
↳ node.
# c.) Find the nearest vertex and connect the random point to the nearest
↳ vertex.
# d.) Scale the distance between the nearest vertex and the random point to
↳ the maximum step size with a unit vector
# if it is larger than the step size.
# e.) Check for collision and RRT Graph whether there is collision or same
↳ node.
# f.) If no collision and it is a different node, add the scaled random
↳ point to the RRT graph.
# g.) If no collision and it is a different node, add the edge of that
↳ connects the scaled random point
# and nearest vertex to the RRT graph. Update the random point parent
↳ is its nearest vertex.
# 3.) Determine the final path from the final vertex to initial vertex. Trace
↳ it with parent nodes.
# 4.) If not enough sample to generate a complete path, return empty path.

# Create obstacles list that store all the obstacle nodes
obs_list_RRT = []

### Draw the obstacles
## Outer Walls
# Top
for depth in range(0, robot_Size + grid_res, grid_res):
```

```

    for idx in range(0 , 800 + grid_res, grid_res):

        obs_node = [idx, depth]
        obs_list_RRT.append(obs_node)

# Right
for width in range(800, 800 - robot_Size - grid_res, -grid_res):

    for idx in range(0 , 300 + grid_res, grid_res):

        obs_node = [width, idx]
        obs_list_RRT.append(obs_node)

# Bottom
for depth in range(300, 300 - robot_Size - grid_res, -grid_res):

    for idx in range(800 , 0 - grid_res, -grid_res):

        obs_node = [idx, depth]
        obs_list_RRT.append(obs_node)

# Left
for width in range(0, robot_Size + grid_res, grid_res):

    for idx in range(300 , 0 - grid_res, -grid_res):

        obs_node = [width, idx]
        obs_list_RRT.append(obs_node)

## Inner Walls (Left to Right)
for width in range(200 - robot_Size, 200 + robot_Size + grid_res, grid_res):

    for idx in range(0 , 200 + grid_res, grid_res):

        obs_node = [width, idx]
        obs_list_RRT.append(obs_node)

for depth in range(200 - robot_Size, 200 + robot_Size + grid_res, grid_res):

    for idx in range(100 - robot_Size, 300 + robot_Size + grid_res, grid_res):

        obs_node = [idx, depth]
        obs_list_RRT.append(obs_node)

for width in range(400 - robot_Size, 400 + robot_Size + grid_res, grid_res):

    for idx in range(100 - robot_Size, 300 + grid_res, grid_res):

```

```

        obs_node = [width, idx]
        obs_list_RRT.append(obs_node)

for width in range(600 - robot_Size, 600 + robot_Size + grid_res, grid_res):

    for idx in range(0 , 200 + grid_res, grid_res):

        obs_node = [width, idx]
        obs_list_RRT.append(obs_node)

for depth in range(200 - robot_Size, 200 + robot_Size + grid_res, grid_res):
    for idx in range(500 - robot_Size, 700 + robot_Size + grid_res, grid_res):

        obs_node = [idx, depth]
        obs_list_RRT.append(obs_node)

# Convert to array
obs_array_RRT = np.array(obs_list_RRT)

class RRT_Algorithm():

    def __init__(self, obs_array_RRT, grid_res, angle_res, robot_Size,
→step_Size, max_iter):

        # obs_array_RRT : An array of obstacle nodes [[ox_1, oy_1], [ox_2,
→oy_2], [ox_3, oy_3], ...]
        # grid_resolution : resolution of the grid in unit
        # angle_resolution: resolution of the grid in degree
        # robot_Size : Maximum radius of the robot
        # step_Size : Maximum length of the edge
        # max_iter : Maximum number of samples/iterations

        # Step 1: Initialization
        # Obstacles array
        self.obs_array_RRT = obs_array_RRT
        # Grid resolution
        self.grid_res = grid_res
        # Angle resolution
        self.angle_res = angle_res
        # Robot size
        self.robot_Size = robot_Size
        # Step size
        self.step_Size = step_Size
        # Maximum iterations
        self.max_iter = max_iter

```

```

# Step 2: Data Extraction
# Determine the lower and upper bounds of the workspace
self.min_x = min(self.obs_array_RRT[:, 0])
self.max_x = max(self.obs_array_RRT[:, 0])
self.min_y = min(self.obs_array_RRT[:, 1])
self.max_y = max(self.obs_array_RRT[:, 1])

# Create a unique ID for the RRT Graph dictionary
def vertex_uniq_ID(self, RRT_vertex):

    # x_coord digit 1 , x_coord digit 2, x_coord digit 3, y_coord digit 1 ,
    →y_coord digit 2, y_coord digit 3
    uniq_ID = RRT_vertex.x * 1000 + RRT_vertex.y

    return uniq_ID

# Euclidean distance
def euclidean_dist(self, v1_x, v1_y, v2_x, v2_y):

    return math.sqrt(abs(v1_x - v2_x)**2 +abs(v1_y - v2_y)**2)

# Call function
def __call__(self, strt_pt, end_pt):

    # Create a RRT Graph dictionary
    RRT_Graph = {}

    # Convert obstacles array to list
    obs_list_RRT = self.obs_array_RRT.tolist()

    # Initial vertex
    init_Vertex = self.RRT_vertex(strt_pt[0], strt_pt[1], -1 )

    # Final vertex
    final_Vertex = self.RRT_vertex(end_pt[0], end_pt[1], -1 )

    # Include the initial vertex to the RRT graph
    RRT_Graph[self.vertex_uniq_ID(init_Vertex)] = init_Vertex

    # Define RRT_flag to stop the while loop when it reaches the final
    →vertex
    RRT_flag = False

    # Set the RRT iteration to 0
    RRT_iter = 0

    # Start the iteration

```

```

while not RRT_flag:

    # Get a random vertex x-coordinate
    q_rand_x = random.randrange(self.min_x, self.max_x, grid_res)
    # Get a random vertex y-coordinate
    q_rand_y = random.randrange(self.min_y, self.max_y, grid_res)
    # Random vertex
    q_rand = np.array([q_rand_x, q_rand_y])
    #print(q_rand)
    rand_Vertex = self.RRT_vertex(q_rand_x, q_rand_y, -1)
    # Create a vertex id
    q_rand_ID = self.vertex_uniq_ID(rand_Vertex)

    # Check whether the vertex is in the RRT Graph dictionary
    if q_rand_ID in RRT_Graph:

        # Update RRT iteration
        #RRT_iter = RRT_iter + 1

        # Skip this loop
        continue

    ## Determine the nearest vertex from q_rand
    # Create an empty list that stores all the distances from the
    ↪random vertex to the RRT vertices
    dist_list = []

    for key in RRT_Graph.keys():

        # Extract the vertex from the RRT graph
        vertex = RRT_Graph[key]
        # Calculate the euclidean distance
        euclid_dist = self.euclidean_dist(q_rand_x, q_rand_y, vertex.x,
    ↪vertex.y)

        # Add to the distance list
        dist_list.append([euclid_dist, key])

    # Sort the distance list
    dist_list.sort()
    # Convert the distance list to array
    dist_arr = np.array(dist_list)

    # Check whether the distance is less than 1
    if dist_arr[0,0] < 1:

        # Skip this loop
        continue

```



```

# Extract the nearest vertex key
nearest_vertex_key = dist_arr[0,1]
# Get the nearest vertex
nearest_vertex = RRT_Graph[nearest_vertex_key]

# Determine the unit vector of the random vertex from the nearest
→vertex
unit_vector_x = int((q_rand_x - nearest_vertex.x) / dist_arr[0,0])
unit_vector_y = int((q_rand_y - nearest_vertex.y) / dist_arr[0,0])

# Check if the distance is more than the step size
if dist_arr[0,0] > self.step_Size:

    # Scale the distance down to its maximum step size
    q_rand_x = nearest_vertex.x + self.step_Size * unit_vector_x
    q_rand_x = grid_res * round(q_rand_x / grid_res) # Round up to
→the grid resolution
    q_rand_y = nearest_vertex.y + self.step_Size * unit_vector_y
    q_rand_y = grid_res * round(q_rand_y / grid_res) # Round up to
→the grid resolution
    q_rand = np.array([q_rand_x, q_rand_y])
    # Update the vertex id
    rand_Vertex = self.RRT_vertex(q_rand_x, q_rand_y, -1)
    q_rand_ID = self.vertex_uniq_ID(rand_Vertex)

# Check whether the vertex is in the RRT Graph dictionary
if q_rand_ID in RRT_Graph:

    # Skip this loop
    continue

# Check for possible collision
if np.any(np.all(q_rand == obs_list_RRT, axis=1)):

    # Skip this while loop
    continue

# Generate vertices along the edge
edge_vertices = line_nd((nearest_vertex.x, nearest_vertex.y),
→(q_rand_x, q_rand_y), endpoint=True)
# Convert to array
edge_vertices = np.array(edge_vertices)
# Reshape it to number of vertices x 2
edge_vertices = edge_vertices.T
# Round up to grid resolution
edge_vertices = grid_res * np.round(edge_vertices/grid_res)

```

```

        # Check for possible collision
        # Initialize collision status
        collision_status = False

        # Check each and every vertices along the edge
        for idx in range(0, edge_vertices.shape[0]):

            # If collision detected
            if np.any(np.all(edge_vertices[idx, :] == obs_list_RRT,
↪axis=1))):

                # Update collision status
                collision_status = True

                # Break the second for loop
                break

            # If there is a collision
            if collision_status == True:

                # Skip the while loop
                continue

        # Update the final version of the random vertex that has a proper
↪parent vertex
        rand_Vertex = self.RRT_vertex(q_rand_x, q_rand_y,
↪nearest_vertex_key)
        q_rand_ID = self.vertex_uniq_ID(rand_Vertex)
        # Add the vertex to the RRT graph
        RRT_Graph[q_rand_ID] = rand_Vertex

        # Label only once
        if RRT_iter == 0:

            # Plot the RRT edge
            plt.plot([nearest_vertex.x, q_rand_x], [nearest_vertex.y,
↪q_rand_y], "-b", label = "RRT edge")

        else:

            # Plot the RRT edge
            plt.plot([nearest_vertex.x, q_rand_x], [nearest_vertex.y,
↪q_rand_y], "-b")

        # Update RRT iteration
        RRT_iter = RRT_iter + 1

```

```

        # Check whether it is near to the final vertex
        if self.euclidean_dist(q_rand_x, q_rand_y, final_Vertex.x,
↪final_Vertex.y) <= self.step_Size:

            # Update the final version of the final vertex that has no
↪proper parent vertex
            final_Vertex = self.RRT_vertex(final_Vertex.x, final_Vertex.y,
↪-1)

            final_Vertex_ID = self.vertex_uniq_ID(final_Vertex)

            # Generate vertices along the edge
            edge_vertices = line_nd((final_Vertex.x, final_Vertex.y),
↪(q_rand_x, q_rand_y), endpoint=True)
            # Convert to array
            edge_vertices = np.array(edge_vertices)
            # Reshape it to number of vertices x 2
            edge_vertices = edge_vertices.T
            # Round up to grid resolution
            edge_vertices = grid_res * np.round(edge_vertices/grid_res)

            # Check for possible collision
            # Initialize collision status
            collision_status = False

            # Check each and every vertices along the edge
            for idx in range(0, edge_vertices.shape[0]):

                # If collision detected
                if np.any(np.all(edge_vertices[idx, :] == obs_list_RRT,
↪axis=1))):

                    # Update collision status
                    collision_status = True

                    # Break the second for loop
                    break

            # If there is a collision
            if collision_status == True:

                # Update RRT iteration
                RRT_iter = RRT_iter + 1

            else:

```

```

        # Update the final version of the final vertex that has a
        ↪ proper parent vertex
        final_Vertex = self.RRT_vertex(final_Vertex.x, final_Vertex.
        ↪ y, q_rand_ID)

        final_Vertex_ID = self.vertex_uniq_ID(final_Vertex)

        # Add the final vertex to the RRT graph
        RRT_Graph[final_Vertex_ID] = final_Vertex
        # Final vertex found
        RRT_flag = True
        print("Goal Reached")
        # Print number of iteration
        print("Number of iteration: ", RRT_iter)
        # Update RRT iteration
        RRT_iter = RRT_iter + 1

    if RRT_iter >= self.max_iter:

        #stop RRT
        RRT_flag = True
        # Print number of iteration
        print("Number of iteration: ", RRT_iter)

    # Determine the final path
    # Store best path from final vertex to initial vertex
    final_path = []

    # Add the final vertex to the final path
    final_path.append(np.array([final_Vertex.x, final_Vertex.y]))

    # Parent vertex of the final vertex
    parent_vertex_ID = final_Vertex.parent_vertex

    # While not the initial vertex
    while parent_vertex_ID != -1:

        # Vertex from RRT Graph
        parent_vertex = RRT_Graph[parent_vertex_ID]
        final_path.append(np.array([parent_vertex.x, parent_vertex.y]))
        # Update the parent vertex ID
        parent_vertex_ID = parent_vertex.parent_vertex

    # convert final_path from list to array
    final_path = np.array(final_path)

    return final_path

```

```

# Create subclass for RRT vertex
class RRT_vertex:

    def __init__(self, x, y, parent_vertex):

        # x-coordinate of the vertex
        self.x = x
        # y-coordinate of the vertex
        self.y = y
        # Vertex parent key
        self.parent_vertex = parent_vertex

    def __call__(self):

        # If the node is called, return an array of node information
        return np.array([self.x, self.y, self.parent_vertex])

### A.) Plot the Configuration Space
## 1.) Try plotting workspace first
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
↪2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
↪2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
↪grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls

```

```

for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid_
↳Wall", zorder = 1)
        continue

    plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

#plt.scatter(obs_array_RRT[:,0], obs_array_RRT[:,1], color = 'black', label =
↳"Walls")
plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center_
↳Point of the Robot cannot Pass")

# h.) Run RRT algorithm
rrt_alg = RRT_Algorithm(obs_array_RRT, grid_res, angle_res, robot_Size,
↳step_Size = 20, max_iter = 50)
best_path = rrt_alg(strt_pt, end_pt)
plt.plot(best_path[:, 0], best_path[:, 1], "--r*", label = 'Selected Final_
↳Path') # Plot the final path

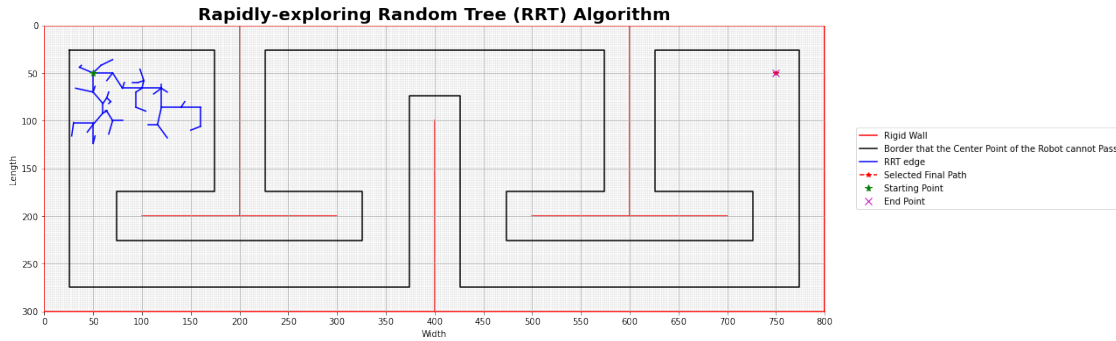
# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Rapidly-exploring Random Tree (RRT) Algorithm", fontsize = 20,
↳fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

# Show the final plot
plt.show()

```

Number of iteration: 50



b.) 100 samples

```
[48]: ### A.) Plot the Configuration Space
## 1.) Try plotting workspace first
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
↳2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
↳2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
↳grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')
```

```

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid_
        ↳Wall", zorder = 1)
        continue

    plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

#plt.scatter(obs_array_RRT[:,0], obs_array_RRT[:,1], color = 'black', label =
↳"Walls")
plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center_
↳Point of the Robot cannot Pass")

# h.) Run RRT algorithm
rrt_alg = RRT_Algorithm(obs_array_RRT, grid_res, angle_res, robot_Size,
↳step_Size = 20, max_iter = 100)
best_path = rrt_alg(strt_pt, end_pt)
plt.plot(best_path[:, 0], best_path[:, 1], "--r*", label = 'Selected Final_
↳Path') # Plot the final path

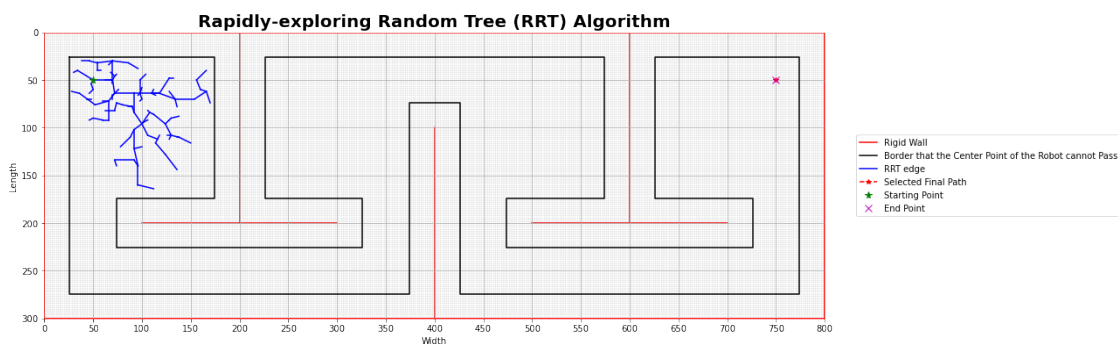
# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Rapidly-exploring Random Tree (RRT) Algorithm", fontsize = 20,
↳fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

# Show the final plot
plt.show()

```

Number of iteration: 100



c.) 150 samples

```
[49]: ### A.) Plot the Configuration Space
## 1.) Try plotting workspace first
# a.) Define figure and axis, and set figure size
fig, ax = plt.subplots(figsize = (16, 6))

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
↳2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
↳2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
↳grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid"
↳Wall", zorder = 1)
        continue
```

```

plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

#plt.scatter(obs_array_RRT[:,0], obs_array_RRT[:,1], color = 'black', label = "Walls")
plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center Point of the Robot cannot Pass")

# h.) Run RRT algorithm
rrt_alg = RRT_Algorithm(obs_array_RRT, grid_res, angle_res, robot_Size, step_Size = 20, max_iter = 150)
best_path = rrt_alg(strt_pt, end_pt)
plt.plot(best_path[:, 0], best_path[:, 1], "--r*", label = 'Selected Final Path') # Plot the final path

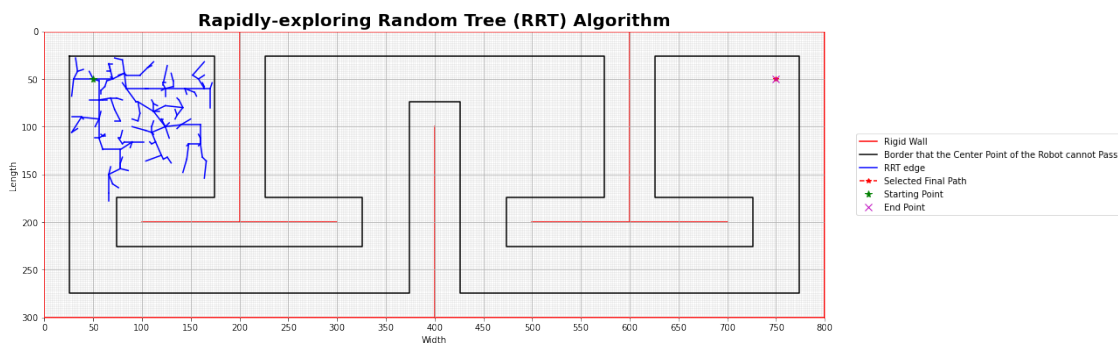
# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

# j.) Plot title
plt.title("Rapidly-exploring Random Tree (RRT) Algorithm", fontsize = 20, fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

# Show the final plot
plt.show()

```

Number of iteration: 150



d.) 10000 samples

[50]: *### A.) Plot the Configuration Space*
1.) Try plotting workspace first
a.) Define figure and axis, and set figure size
 fig, ax = plt.subplots(figsize = (16, 6))

```

# b.) Label axis
plt.xlabel('Width')
plt.ylabel('Length')

# c.) Set axis limit
plt.xlim(map_size_Width)
plt.ylim(map_size_Length)
plt.gca().invert_yaxis()

# d.) Plot major grid
ax.set_xticks(major_grid_Width)
ax.set_yticks(major_grid_Length)
plt.grid(visible = True, which = 'major', linestyle='-') # Major grid parameters

# e.) Plot minor grid
ax.set_xticks(minor_grid_Width, minor = True) # Set the grid resolution to 2 x
→2
ax.set_yticks(minor_grid_Length, minor = True) # Set the grid resolution to 2 x
→2
plt.grid(visible = True, which = 'minor', linestyle='-', alpha=0.2) # Minor
→grid parameters
ax.tick_params(which='minor', bottom=False, left=False) # Hide grid

# f.) Plot walls in red
# Outer walls
for spine in ax.spines.values():

    spine.set_edgecolor('red')

# Inner walls
for idx in range(0, thin_walls.shape[0]):

    if idx == 1:

        plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', label = "Rigid
→Wall", zorder = 1)
        continue

    plt.plot(thin_walls[idx][0], thin_walls[idx][1], '-r', zorder = 1)

#plt.scatter(obs_array_RRT[:,0], obs_array_RRT[:,1], color = 'black', label =
→"Walls")
plt.plot(obs_corns[:,0], obs_corns[:,1], '-k', label = "Border that the Center
→Point of the Robot cannot Pass")

# h.) Run RRT algorithm

```

```

rrt_alg = RRT_Algorithm(obs_array_RRT, grid_res, angle_res, robot_Size,
    ↳step_Size = 20, max_iter = 10000)
best_path = rrt_alg(strt_pt, end_pt)
plt.plot(best_path[:, 0], best_path[:, 1], "--r*", label = 'Selected Final
    ↳Path') # Plot the final path

# i.) Plot the starting location and the ending location
plt.plot(strt_pt[0], strt_pt[1], 'g*', label = "Starting Point", markersize = 8)
plt.plot(end_pt[0], end_pt[1], 'mx', label = "End Point", markersize = 8)

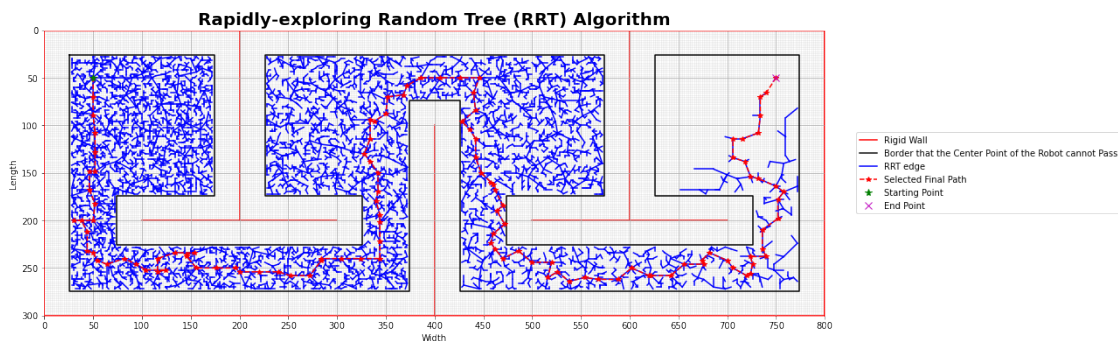
# j.) Plot title
plt.title("Rapidly-exploring Random Tree (RRT) Algorithm", fontsize = 20,
    ↳fontweight = "bold")
plt.legend(bbox_to_anchor=(1.04,0.5), loc="center left", borderaxespad=0)

# Show the final plot
plt.show()

```

Goal Reached

Number of iteration: 7610



[51]: # Calculate the total length of the RRT path

```
RRT_path_length = 0
```

```
for idx in range(0, best_path.shape[0] - 1):
```

```
    # Euclidean Distance
```

```
    x_delta = best_path[idx, 0] - best_path[idx + 1, 0]
```

```
    x_delta_sq = x_delta*x_delta
```

```
    y_delta = best_path[idx, 1] - best_path[idx + 1, 1]
```

```
    y_delta_sq = y_delta*y_delta
```

```
    edge_length = math.sqrt(x_delta_sq + y_delta_sq)
```

```
    # Cumulated distance
```

```
RRT_path_length = RRT_path_length + edge_length  
  
print("RRT Algorithm Path Length: ", RRT_path_length, " units")
```

RRT Algorithm Path Length: 1721.7174909623232 units

Comments on the main differences in performance between PRM and RRT: RRT requires a lot more number of samples than the PRM to generate a path from the initial point to the final point because RRT builds a new graph from the initial point in every iteration and aims to land a point that is randomly generated within the final point area. On the other hand, PRM just requires a sufficient amount of randomly generated nodes to build a roadmap that will cover most of the free space; then, the final path will be determined by the greedy algorithm. Hence, PRM requires lesser computational cost than RRT. Besides that, based on my generated final paths from RRT plot with 10000 samples and PRM plot with 150 samples, PRM final path length is 246 units shorter than the RRT final path length. Hence, PRM has a more efficient path than the RRT.