

# ME766A: Robot Motion Planning

## Assignment-4: Potential Field Methods

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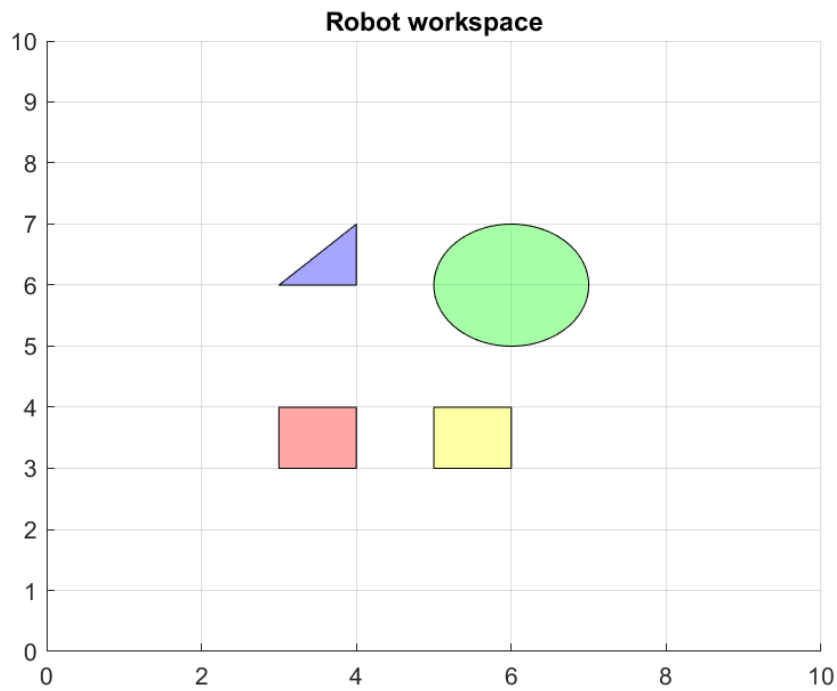


Figure 1: Robot workspace for autonomous path creation

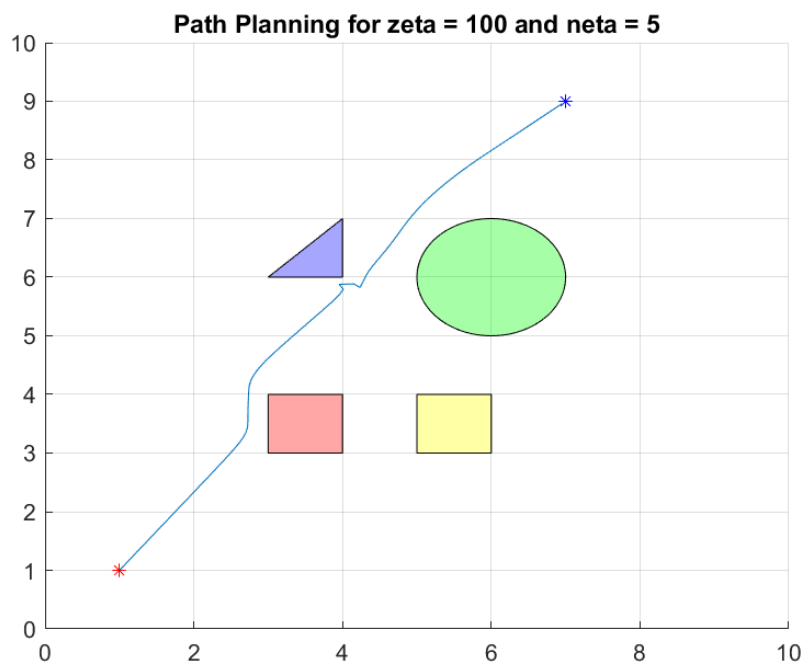


Figure 2: Path plotting for  $\zeta=100$  and  $\eta=5$

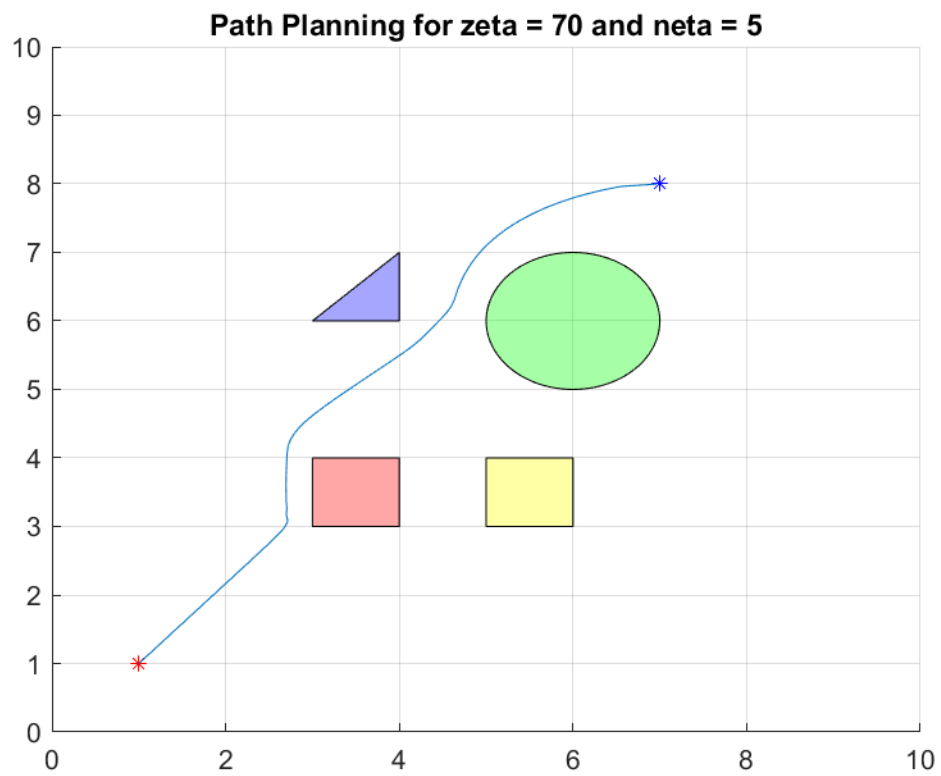


Figure 3: Path plotting for  $\zeta=70$  and  $\eta=5$

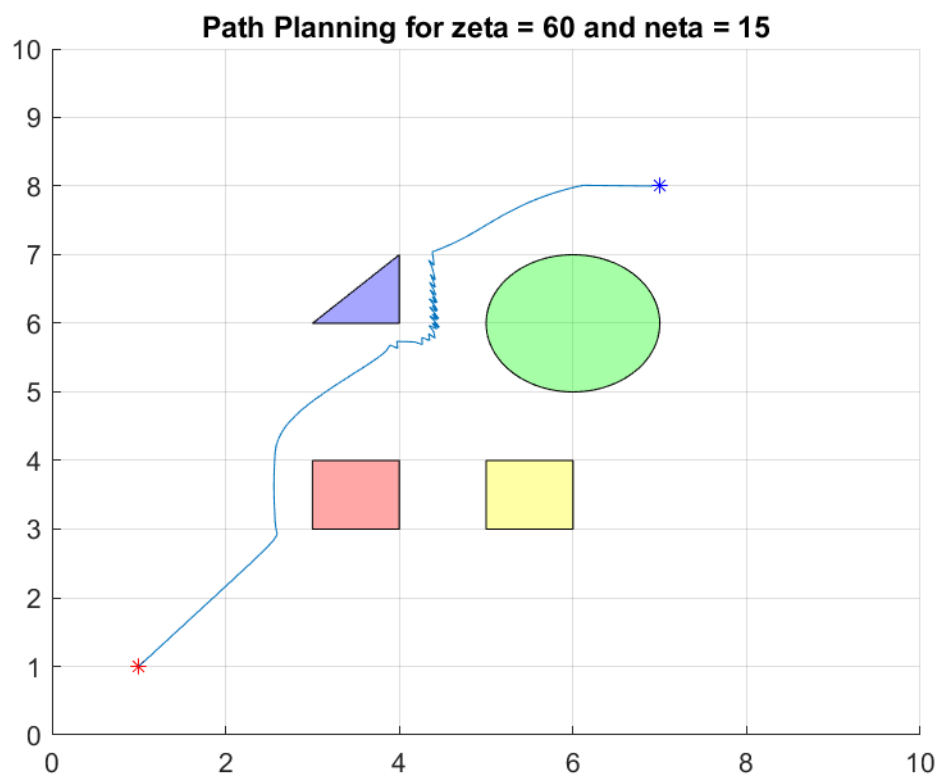


Figure 4: Path plotting for  $\zeta=60$  and  $\eta=15$

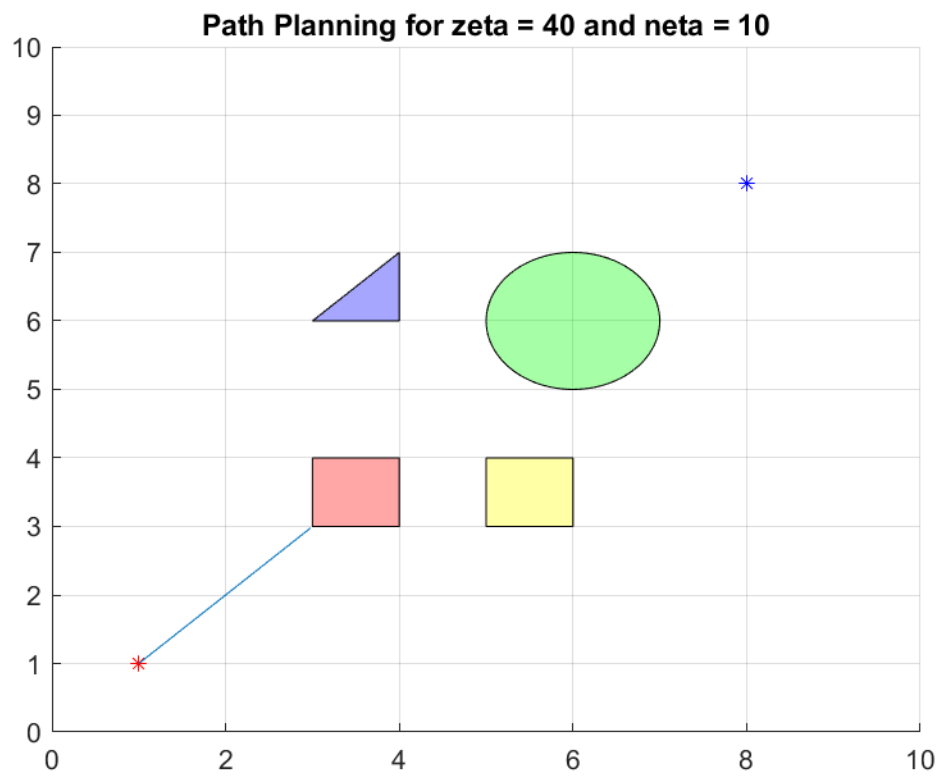


Figure 5: Trapping the robot at a local minima