

A* Motion Planning

```
In [ ]: # The autoreload extension will automatically load in new code as you edit files,
# so you don't need to restart the kernel every time
%load_ext autoreload
%autoreload 2
import numpy as np
import matplotlib.pyplot as plt
from Pl_astar import DetOccupancyGrid2D, AStar
from utils import generate_planning_problem
```

Simple Environment

Workspace

(Try changing this and see what happens)

```
In [ ]: width = 10
height = 10
obstacles = [((6,7),(8,8)),((2,2),(4,3)),((2,5),(4,7)),((6,3),(8,5))]
occupancy = DetOccupancyGrid2D(width, height, obstacles)
#print(occupancy.is_free)
```

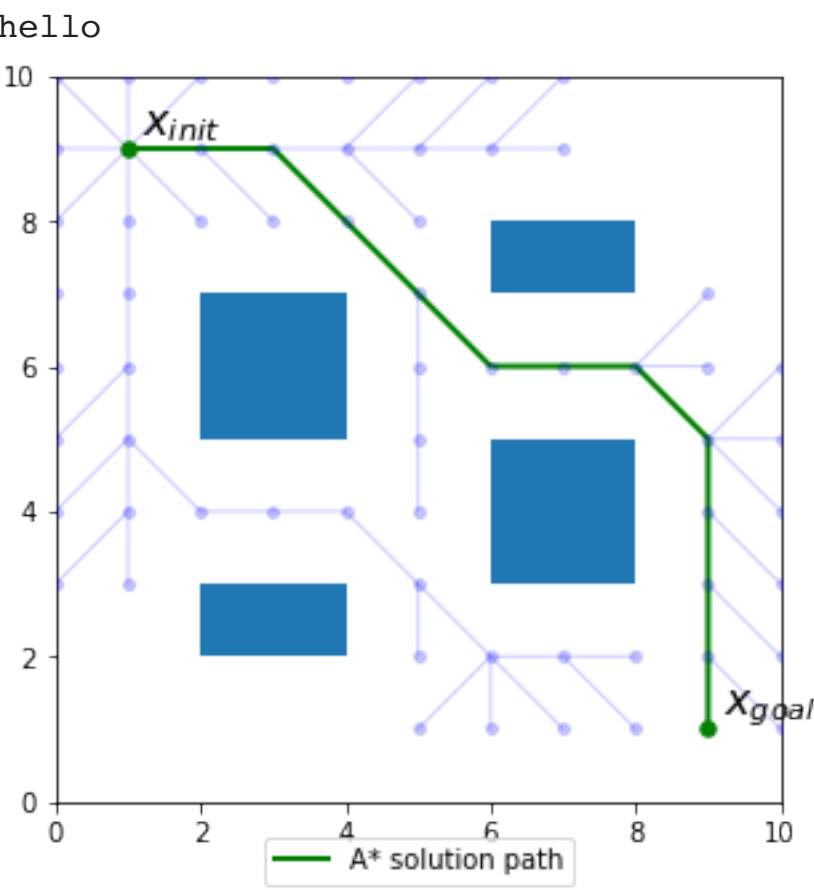
Starting and final positions

(Try changing these and see what happens)

```
In [ ]:
In [ ]: x_init = (1, 9)
x_goal = (9, 1)
```

Run A* planning

```
In [ ]: astar = AStar((0, 0), (width, height), x_init, x_goal, occupancy)
print("hello")
if not astar.solve():
    print("No path found")
else:
    plt.rcParams['figure.figsize'] = [5, 5]
    astar.plot_path()
    astar.plot_tree()
```



Random Cluttered Environment

Generate workspace, start and goal positions

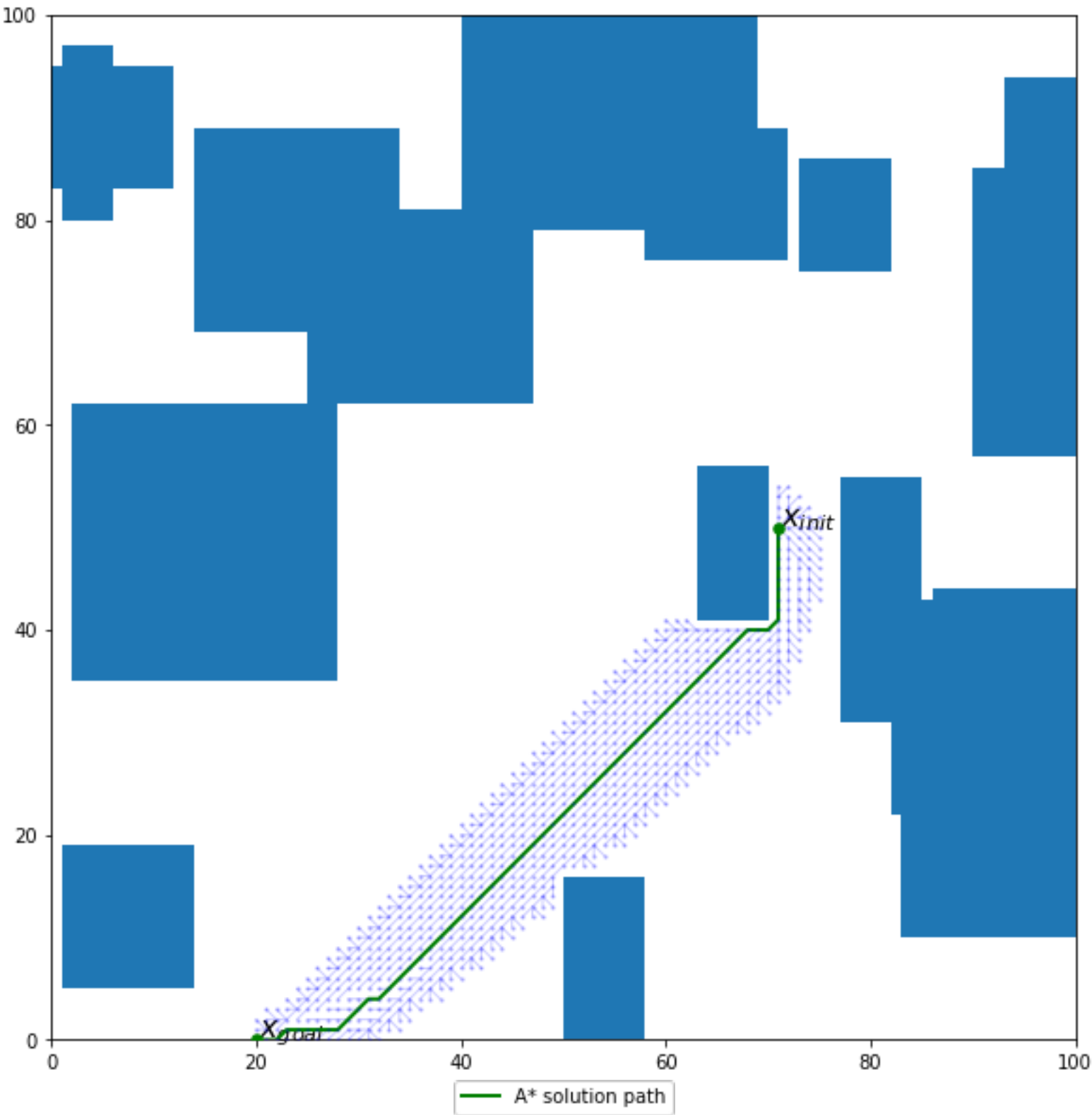
(Try changing these and see what happens)

```
In [ ]: width = 100
height = 100
num_obs = 25
min_size = 5
max_size = 30

occupancy, x_init, x_goal = generate_planning_problem(width, height, num_obs, min_size, max_size)
```

Run A* planning

```
In [ ]: astar = AStar((0, 0), (width, height), x_init, x_goal, occupancy)
if not astar.solve():
    print("No path found")
else:
    plt.rcParams['figure.figsize'] = [10, 10]
    astar.plot_path()
    astar.plot_tree(point_size=2)
```



```
In [ ]:
```