



# Installation

Ensure you have Python and the required libraries installed:

```
pip install numpy matplotlib
```

## Usage

### Example Code

```
import numpy as np
import matplotlib.pyplot as plt
from mpl_toolkits.mplot3d import Axes3D
from matplotlib.animation import FuncAnimation

# Define the PotentialFieldPathPlanner class and other functions here

# Example usage
obstacles = [
    (2, 2, 0, 1, 1, 6),
    (5, 2, 0, 1, 1, 6),
    (1, 5, 0, 1, 1, 6),
    (5, 5, 0, 1, 1, 6),
    (2, 7, 0, 1, 1, 6),
    (7, 3, 0, 1, 1, 6),
    (4, 1, 0, 1, 1, 6),
    (1, 1, 0, 1, 1, 6),
    (4, 7, 0, 1, 1, 6),
    (7, 7, 0, 1, 1, 6)
]

start = (2, 4, 0)
goals = [(8, 6, 3), (1, 8, 0), (3, 1, 0)]

attractive_gains = np.linspace(1.0, 2.0, 5)
repulsive_gains = np.linspace(0.1, 2.0, 5)

best_gains, best_fitness = find_best_gains(obstacles, start, goals,
attractive_gains, repulsive_gains)
print(f"Best gains: Attractive Gain = {best_gains[0]}, Repulsive Gain =
{best_gains[1]}")
print(f"Best MSE Cost: {best_fitness}")

# Visualize the path for the best gains and the first goal
planner = PotentialFieldPathPlanner(obstacles, start, goals[0], best_gains[0],
best_gains[1])
path, cost = planner.plan_path()
visualize_path(obstacles, path, start, goals[0])
```

```
# Visualize the path for the best gains and each goal
for goal in goals:
    planner = PotentialFieldPathPlanner(obstacles, start, goal, best_gains[0],
    best_gains[1])
    path, cost = planner.plan_path()
    visualize_path(obstacles, path, start, goal)
```

## Visualization

The `visualize_path` function provides a 3D visualization of the path planned by the robot, including the start and goal positions and the obstacles.

## Mathematical Concepts

### Attractive Force

The attractive force  $\mathbf{F}_{att}$  pulls the robot towards the goal. It is typically modeled as a linear function of the distance to the goal:

$$\mathbf{F}_{att} = k_{att} \cdot (\mathbf{q}_{goal} - \mathbf{q})$$

where:

- $k_{att}$  is the attractive gain.
- $\mathbf{q}_{goal}$  is the position of the goal.
- $\mathbf{q}$  is the current position of the robot.

### Repulsive Force

The repulsive force  $\mathbf{F}_{rep}$  pushes the robot away from obstacles. It is usually modeled to have an effect only within a certain distance  $d_0$  from the obstacle:

$$\mathbf{F}_{rep} = \begin{array}{l} k_{rep} \cdot \left( \frac{1}{\|\mathbf{q} - \mathbf{q}_{obs}\|} - \frac{1}{d_0} \right) \frac{1}{\|\mathbf{q} - \mathbf{q}_{obs}\|^2} \\ \frac{\|\mathbf{q} - \mathbf{q}_{obs}\|}{\|\mathbf{q} - \mathbf{q}_{obs}\|}, \& \text{if } \|\mathbf{q} - \mathbf{q}_{obs}\| \leq d_0 \\ 0, \& \text{if } \|\mathbf{q} - \mathbf{q}_{obs}\| > d_0 \end{array}$$

where:

- $k_{rep}$  is the repulsive gain.
- $\mathbf{q}_{obs}$  is the position of the obstacle.
- $d_0$  is the influence distance of the obstacle.

### Total Force

The total force  $\mathbf{F}$  acting on the robot is the sum of the attractive and repulsive forces:

$$\mathbf{F} = \mathbf{F}_{att} + \mathbf{F}_{rep}$$

## Path Planning

The robot's movement is determined by the total force. At each time step, the robot's position is updated based on the force:

$$\mathbf{q}_{new} = \mathbf{q} + \Delta t \cdot \mathbf{F}$$

where  $\Delta t$  is the time step.

## Optimization

To find the best gains  $k_{att}$  and  $k_{rep}$ , we minimize a cost function, typically the Mean Squared Error (MSE) between the planned path and the desired path:

$$\text{MSE} = \frac{1}{N} \sum_{i=1}^N \|\mathbf{q}_i - \mathbf{q}_{goal}\|^2$$

where  $N$  is the number of steps in the path.

## Skills Demonstrated

- **Programming:** Proficient use of Python, including libraries such as NumPy and Matplotlib.
- **Robotics Engineering:** Implementation of potential field path planning, a fundamental concept in robotics navigation.
- **Optimization:** Finding the best parameters for the path planner to minimize the cost function.
- **3D Visualization:** Using Matplotlib to visualize the robot's path and obstacles in a 3D space.

## Contributing

Contributions are welcome! If you have suggestions for improvements or new features, please open an issue or submit a pull request.

## Contact

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