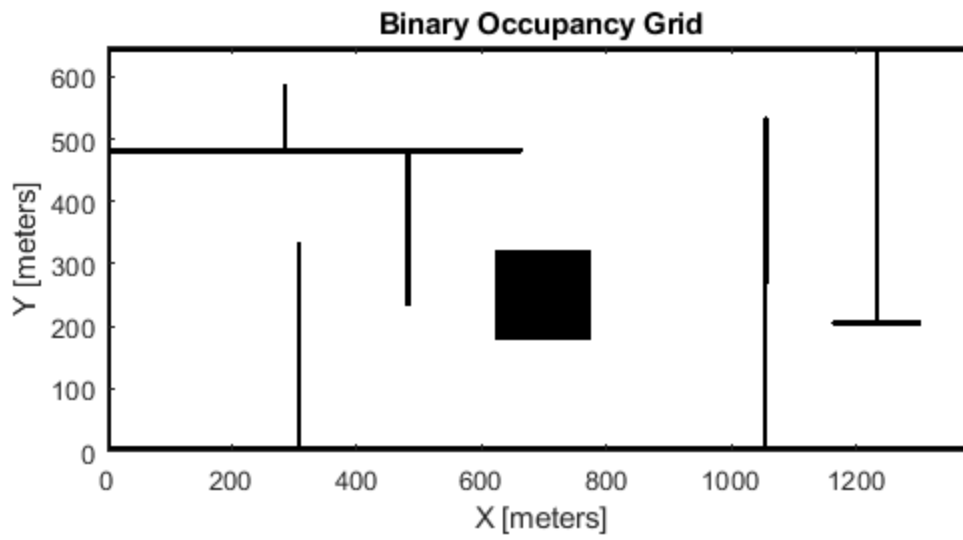
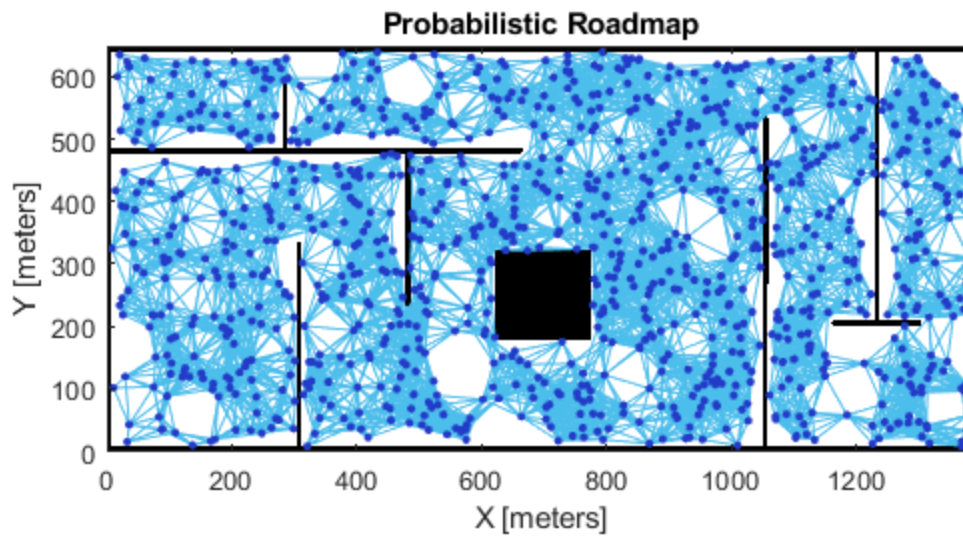

```
clear
clc

%%Load the map(obstacles).
img = imread('mat1.png');
figure
th = 0.6;
bw = im2bw(img,th);
figure,
imshow(bw);
map = binaryOccupancyMap(bw,1);
show(map)
```



```
prm = mobileRobotPRM;  
prm.NumNodes = 1000;  
prm.ConnectionDistance = 80;  
prm.Map= map;  
show(prm)
```

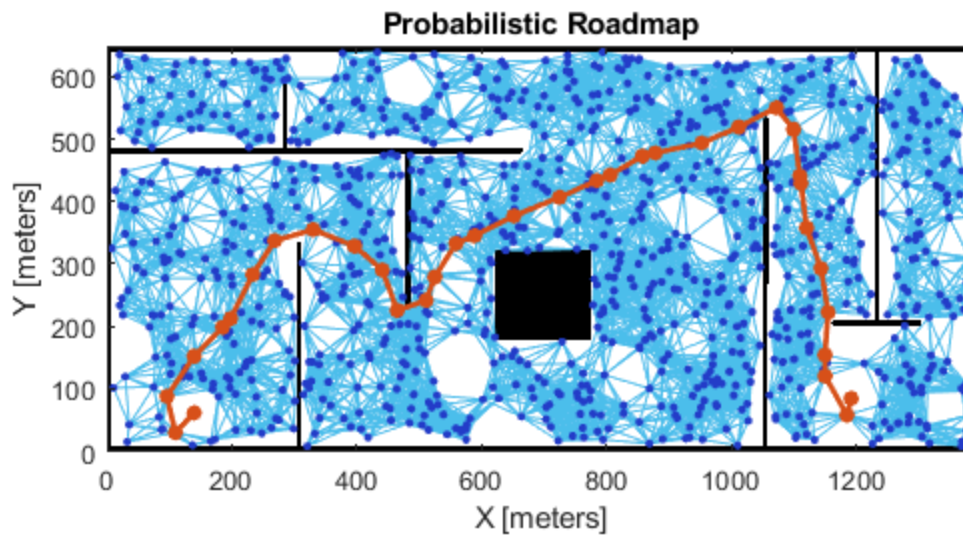


```

disp('Click for the start Location');
startLocation = ginput(1);
disp('Click for the end Location');
endLocation = ginput(1);
% while isempty(path)
%     prm.NumNodes = prm.NumNodes + 30
%     update(prm)
%     path = findpath(prm,startLocation,endLocation)
%     show(prm)
%     pause(1)
% end
path = findpath(prm,startLocation,endLocation);
show(prm);

```

Click for the start Location
Click for the end Location



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