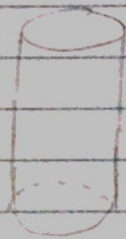


2. Say current position is $\begin{bmatrix} x_i \\ y_i \\ z_i \end{bmatrix} = \mathbf{O}_i^0$, d is the closest point at the surface of obstacles

$$1). \mathbf{O}_i^0 - d = \begin{bmatrix} 0 \\ 0 \\ z_i - z_2 \end{bmatrix} \quad \|\mathbf{O}_i^0 - d\| = z_i - z_2.$$

$$F = \eta_i \left(\frac{1}{z_i - z_2} - \frac{1}{p_0} \right) \frac{1}{|z_i - z_2|^3} [0 \ 0 \ z_i - z_2]$$

2). $\cdot c \quad \cdot b \quad \therefore 3 \text{ condition.}$



Center axis at (x_0, y_0) .
Radius is R .

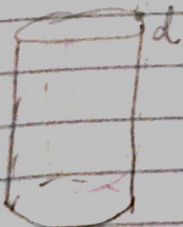
a). $z_i \leq h$

$$\|\mathbf{O}_i^0 - d\| = \left\| \begin{bmatrix} x_i - x_0 \\ y_i - y_0 \\ 0 \end{bmatrix} \right\| - R = \sqrt{(x_i - x_0)^2 + (y_i - y_0)^2} - R$$

$$\mathbf{O}_i^0 - d = \begin{bmatrix} x_i - x_0 \\ y_i - y_0 \\ 0 \end{bmatrix} \frac{\|\mathbf{O}_i^0 - d\|}{\left\| \begin{bmatrix} x_i - x_0 \\ y_i - y_0 \\ 0 \end{bmatrix} \right\|}$$

$$= \begin{bmatrix} x_i - x_0 \\ y_i - y_0 \\ 0 \end{bmatrix} \frac{\sqrt{(x_i - x_0)^2 + (y_i - y_0)^2} - R}{\sqrt{(x_i - x_0)^2 + (y_i - y_0)^2}}$$

b). $z_i > h, (x_i - x_0)^2 + (y_i - y_0)^2 > R^2$



$$\|\mathbf{O}_i^0 - d\| = \sqrt{(\sqrt{(x_i - x_0)^2 + (y_i - y_0)^2} - R)^2 + (z_i - h)^2}$$

$$\mathbf{O}_i^0 - d = \begin{bmatrix} x_i - x_0 \\ y_i - y_0 \\ 0 \end{bmatrix} \frac{\sqrt{(x_i - x_0)^2 + (y_i - y_0)^2} - R}{\sqrt{(x_i - x_0)^2 + (y_i - y_0)^2}} + \begin{bmatrix} 0 \\ 0 \\ z_i - h \end{bmatrix}$$

Hibroy

$$c) z_i > h, (x_i - x_0)^2 + (y_i - y_0)^2 \leq R^2$$

$$O_i^0 - d = \begin{bmatrix} 0 \\ 0 \\ z_i - h \end{bmatrix} \quad \|O_i^0 - d\| = z_i - h$$

$$F = \eta_i \left(\frac{1}{\|O_i^0 - d\|} - \frac{1}{\rho_0} \right) \frac{1}{\|O_i^0 - d\|^3} (O_i^0 - d)^T$$