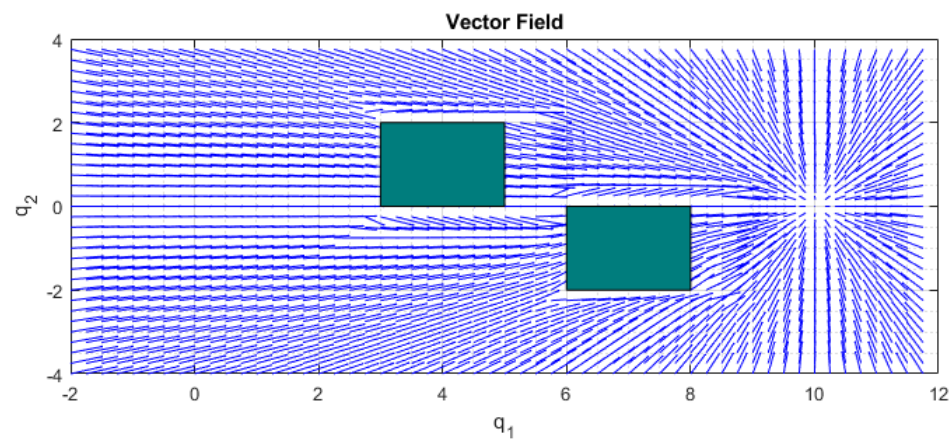

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Housekeeping

i) Plot Vector Field



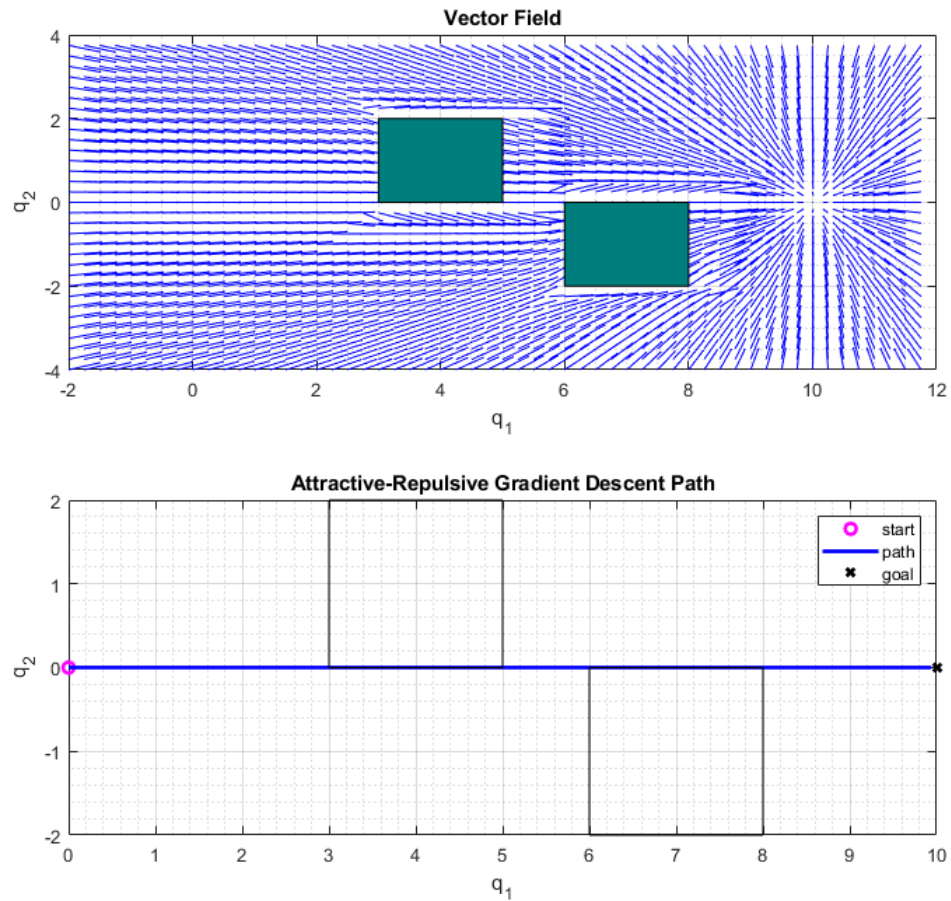
ii)

I started with a large `dstar_goal` and slowly decreased it

until I saw that the attractive forces were decreasing smoothly as the robot reached the gap between the obstacles. The Qstar for both obstacles were the same and the robot was able to move straight towards the goal without deviating from the obstacles

iii) Plot Path

Load path from csv



iv)

The length of the path is: 9.937525

v)

Yes, I would expect different path lengths since the Qstar influences how close a robot can come to a certain obstacle and since the obstacles are near the robots path to goal the robot would surely be swayed if Qstar is decreased

