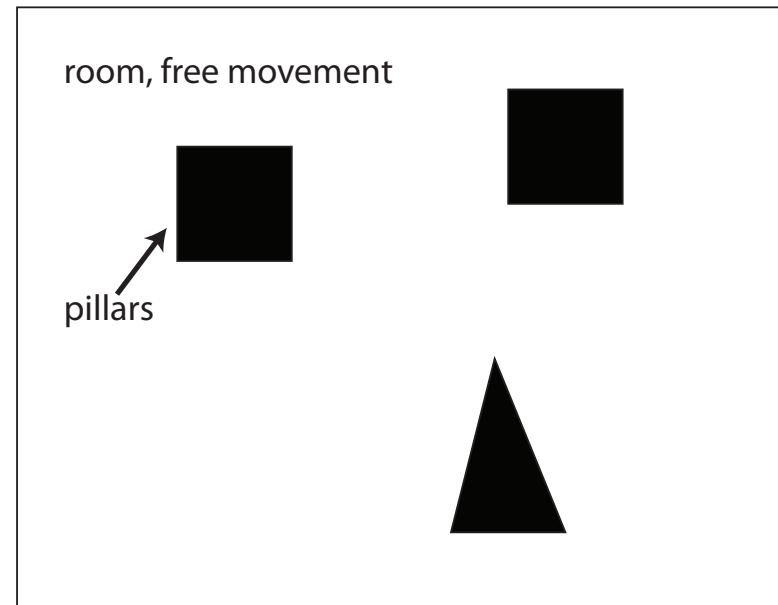


L5-C2 Which algorithm?

You have an application where your robot needs to navigate in an empty and deserted room with 3 pillars, as in the plan on the right. What approach of path planning would you choose to get an optimal path?

○ = size of the robot



- A. **Potential field, as in this case the obstacles cannot generate local minima.**
- B. **Voronoi diagrams, displacement at the center of the cells to create the graph, then graph search by A*.**
- C. **Visibility graphs and dijkstra path search.**