Future Scope of AIV

1. Implementation of a controller ( e.g. PID controller ) to improve the motion execution accuracy of AIV.
2. Improvement of the obstacle avoidance algorithm.
3. Integrating the code for "localization using LIDAR" in the main AIV code.
4. Fitting a smooth curve to the planned polyline from current position to destination. Executing motion along that curve accurately.
5. Probably integrating a camera to raspberry pi and using vision based algorithms to make the AIV more intelligent.