1. Kinect gives data stream

2. Calculate instantaneous 3D coordinate of the point of the object.

-> set 3D origin first

-> set up an object for Kinect to track, and its default position

loop -> get 3D position vector of the object

(x,y,z) -> instantaneous position of the object

-> if the delta distance > tolerance or other conditions, then go to next step.

3. Calculate delta energy to get to the point.

4. Calculate force function F(t) = ? or…

5. Convert F(t) to rpm(t) or F(rpm1(t), rpm2(t), rpm3(t), rpm4(t)) … ??

-> Function rpm = rpm (data from gyro& accelerometer, position vector(kinect), etc.)

6. Send the information (4 scalar values) of rpm vectors to commercial auto pilot

7. Autopilot executes the intended rpm.