Autonomous\_Driving()

START

SET Vehicle to autonomous mode

IF

*Mapdata is provided*

Manual\_Operation =1

hD\_Map\_Path\_data()

Vehicle\_Moves\_forward()

ELSE

Print “No path data present, vehicle cannot proceed.”

RETURN

FUNCTION obstacle\_avoidance()

IF

*Obstacle is detected.*

Sensor\_data\_available()

Wait()  
 Reroute()

Destination()

Print “obstacle detected, journey finished”.

ELSE

Destination()

Print “ No obstacle detected, journey finished”.

End