Work report
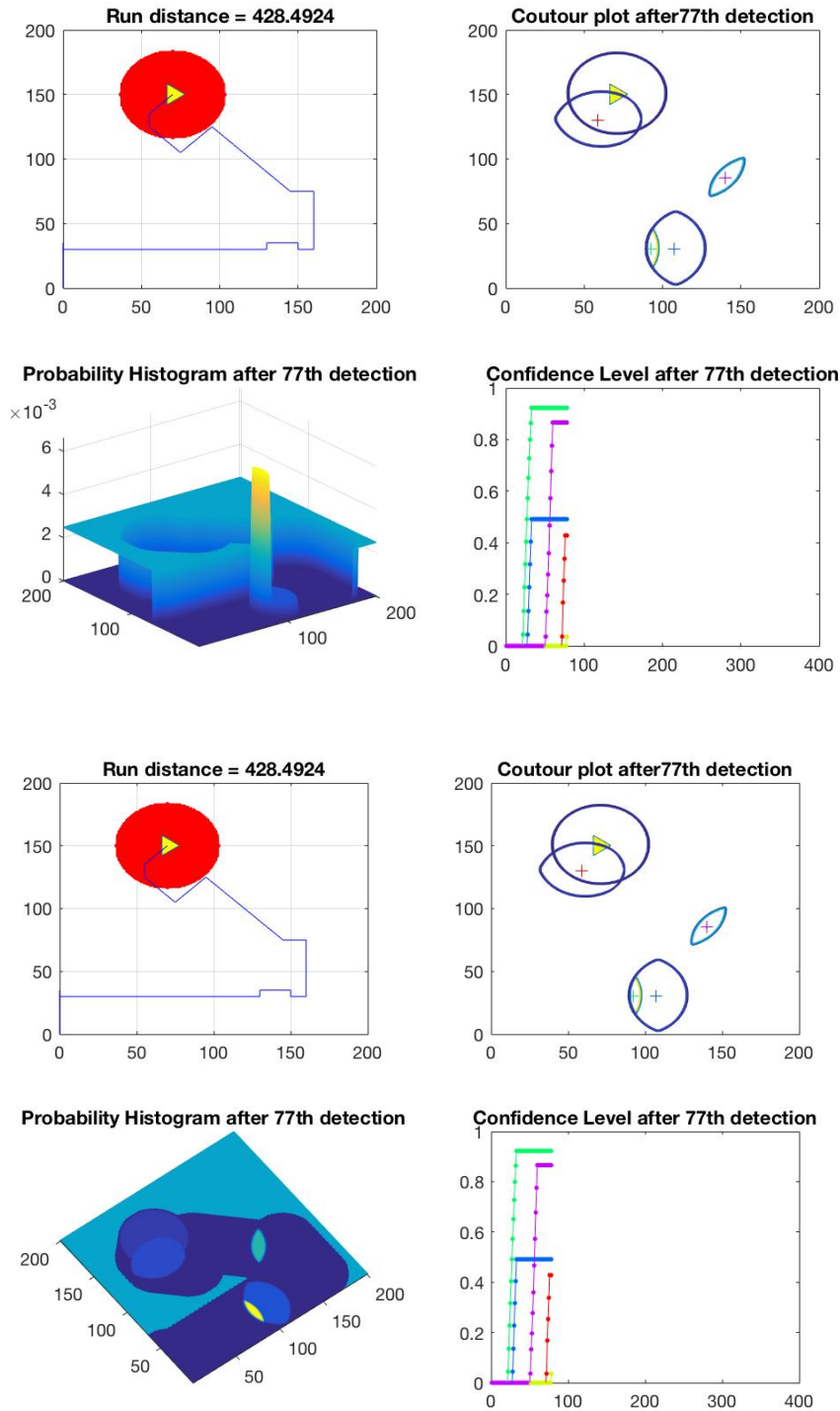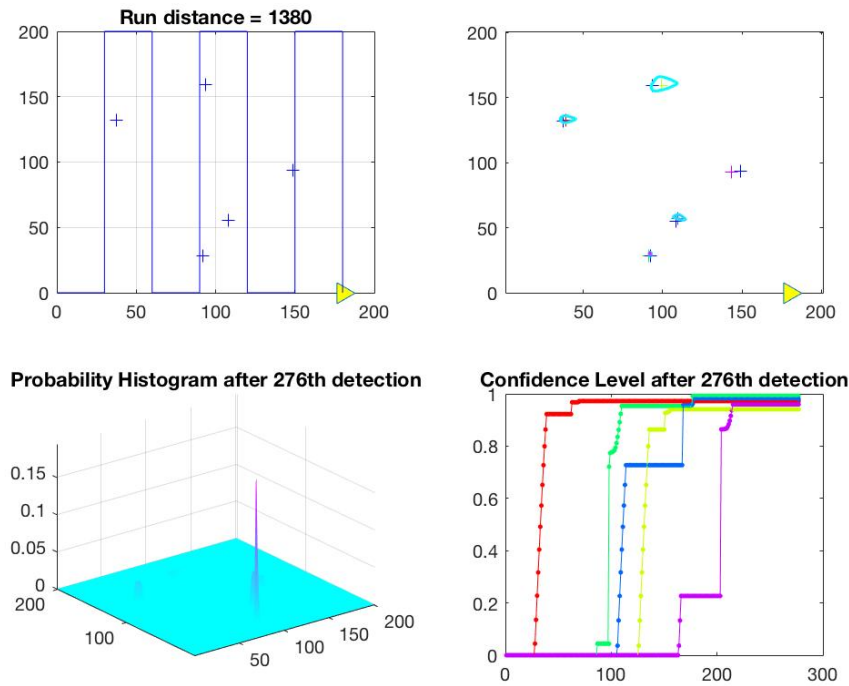
Improved code based on your suggestion.
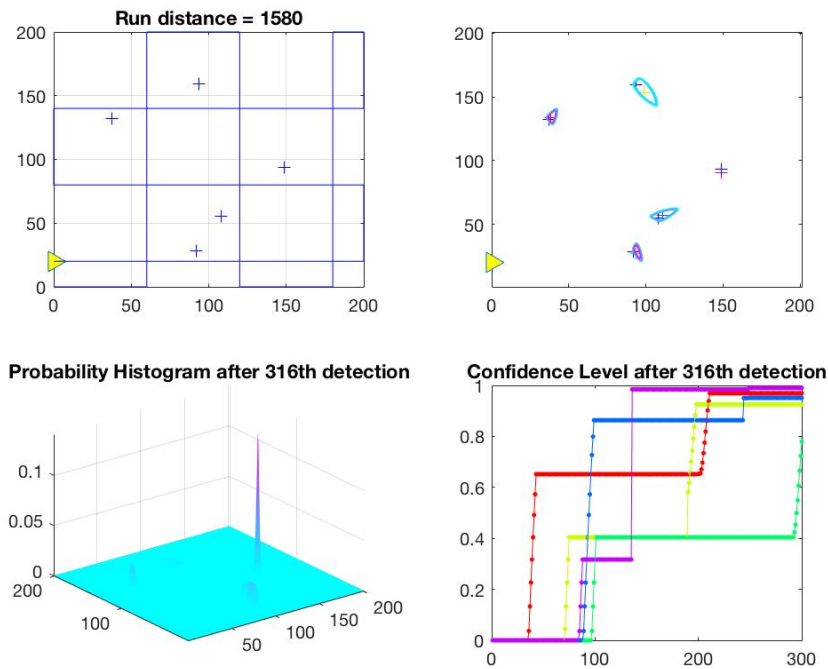**Sweep off figures:**
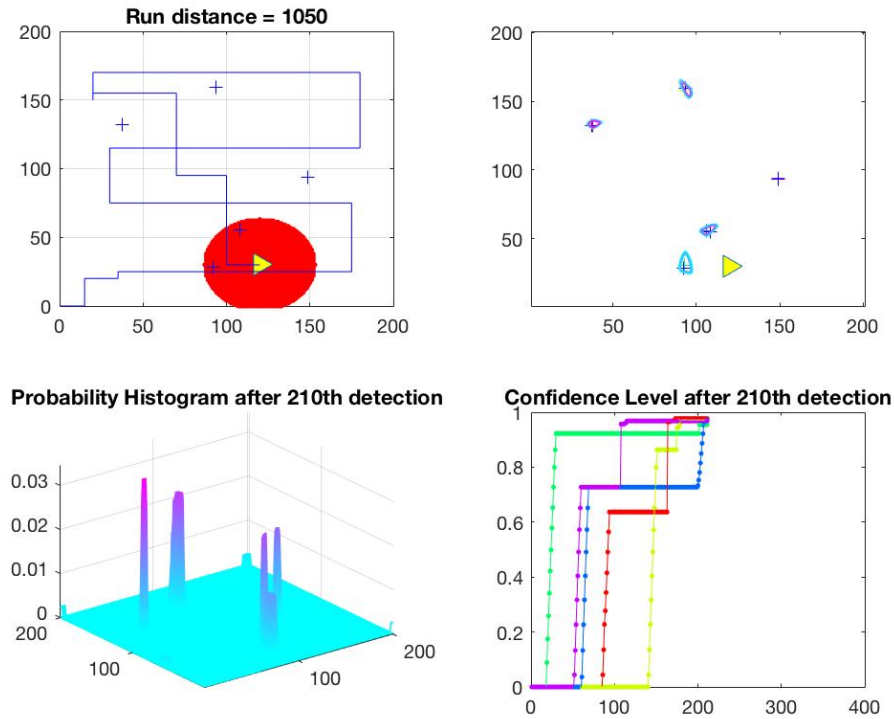
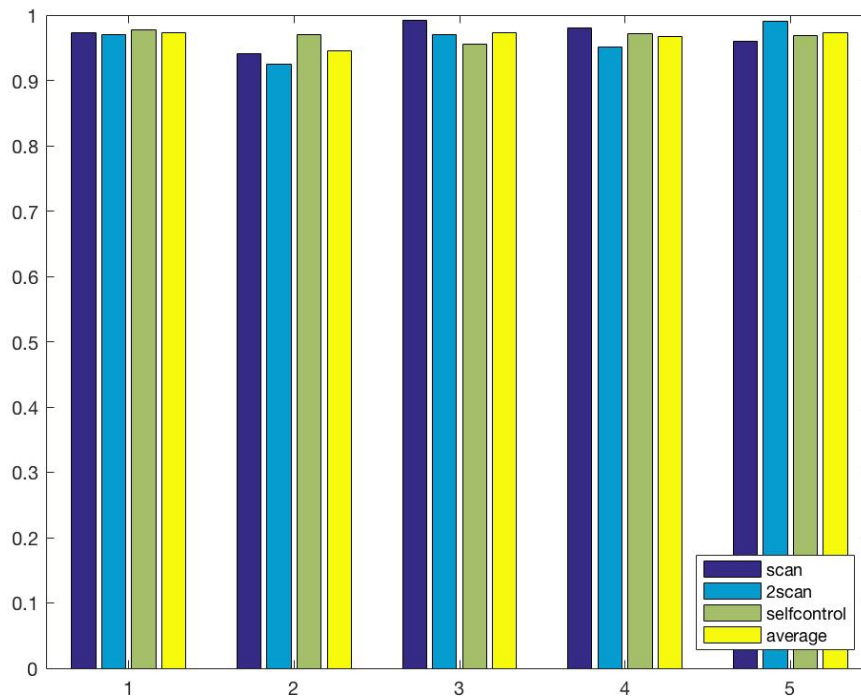**Simple path planning:**
Scan: resolution 30

Double scan: Resolution 60 in order to reduce path length

Control by joystick based on the contour and histogram: resolution 30

result compare:

Conclusion:
1. **From the confidence level compare chart, we can draw the conclusion that three path planning nearly have the same result after scan whole area.**
2. **Double scan has the longest run distance compared with others.**
3. **Controlled by joystick based on contour and histogram can significantly reduce total path length.**

Acknowledge:
All three path are executed by joystick, thus run distance may be longer than the result compute by formula, but it isn't big enough to influence the conclusion.

What I plan to do:
Think about path planning algorithm based on the contour and histogram, in order to autonomously control boat to find the optimal path.