```
 1    stack current_path;  //Save the current path
 2
 3    MSA(start, end)
 4
 5    Push the start position into the stack current_path
 6    Get the top element n of the stack current_path
 7
 8    if n equal to the position of end
 9        save the stack current_path to all_path
10        end
11    else
12        if left hand direction of robot is able to explore
13            i = the position of next point in left hand direction direction
14        if positive direction of robot is able to explore
15            i = the position of next point in positive direction
16        if right hand position of robot is able to explore
17            i = the position of next point in right hand position
18        if opposite direction of robot is able to explore
19            i = the position of next point in  hand opposite position
20        MSA(i, end)
21
```