Figure 1: Initial flowchart proposition of our pixy's algorithm

This is an initial proposition, it is likely that I forgot steps. Each of these steps can obviously be decomposed as flowcharts too. The difficulty of the tasks is unequal. I believe that the hardest task will be task 3.2) and maybe task 5.2). For 3.2) we can anticipate difficulties about the strategy to search for a target, a strategy not to go out of the battlefield and a strategy to avoid obstacles (other targets, other pixy). For 5.2) we can anticipate difficulties about the tracking of the target (we don't want our robot to change its mind midway of destination). I thought it could be a good starting point to attribute the different tasks.