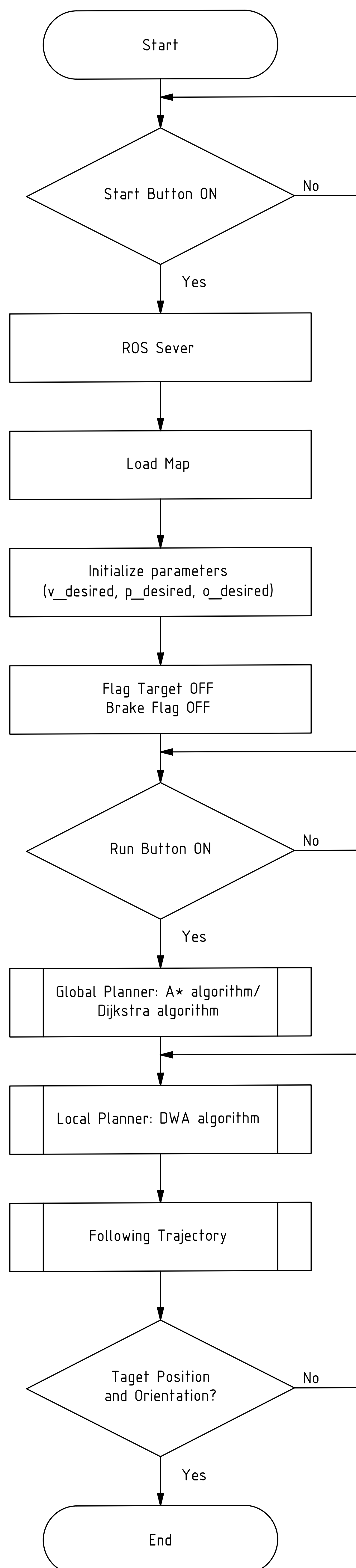
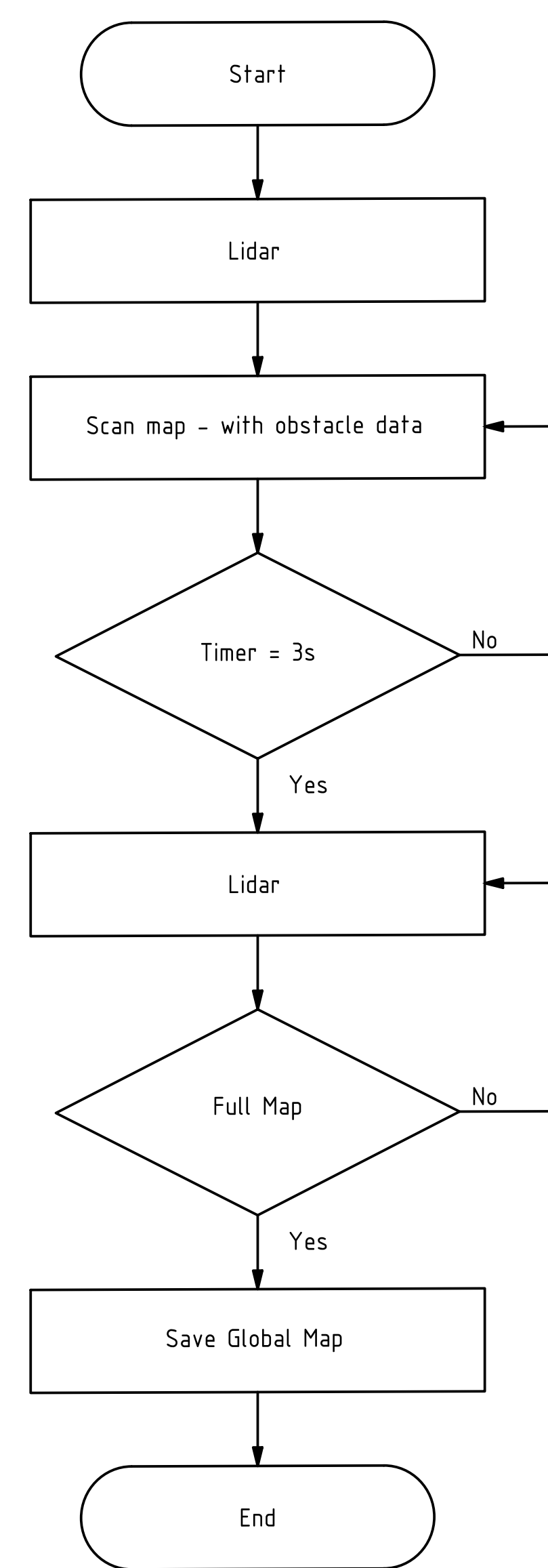


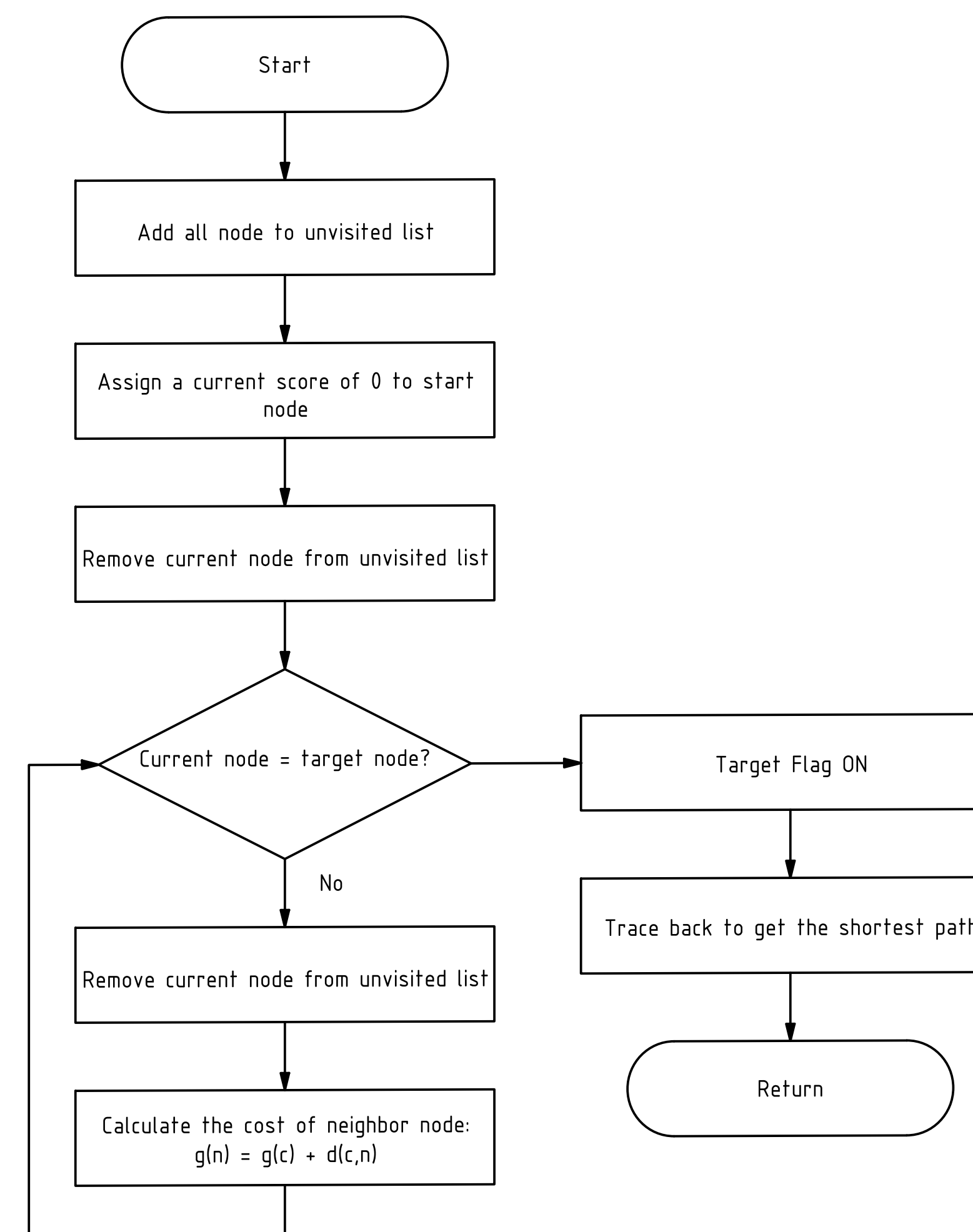
## ALGORITHM FLOWCHART



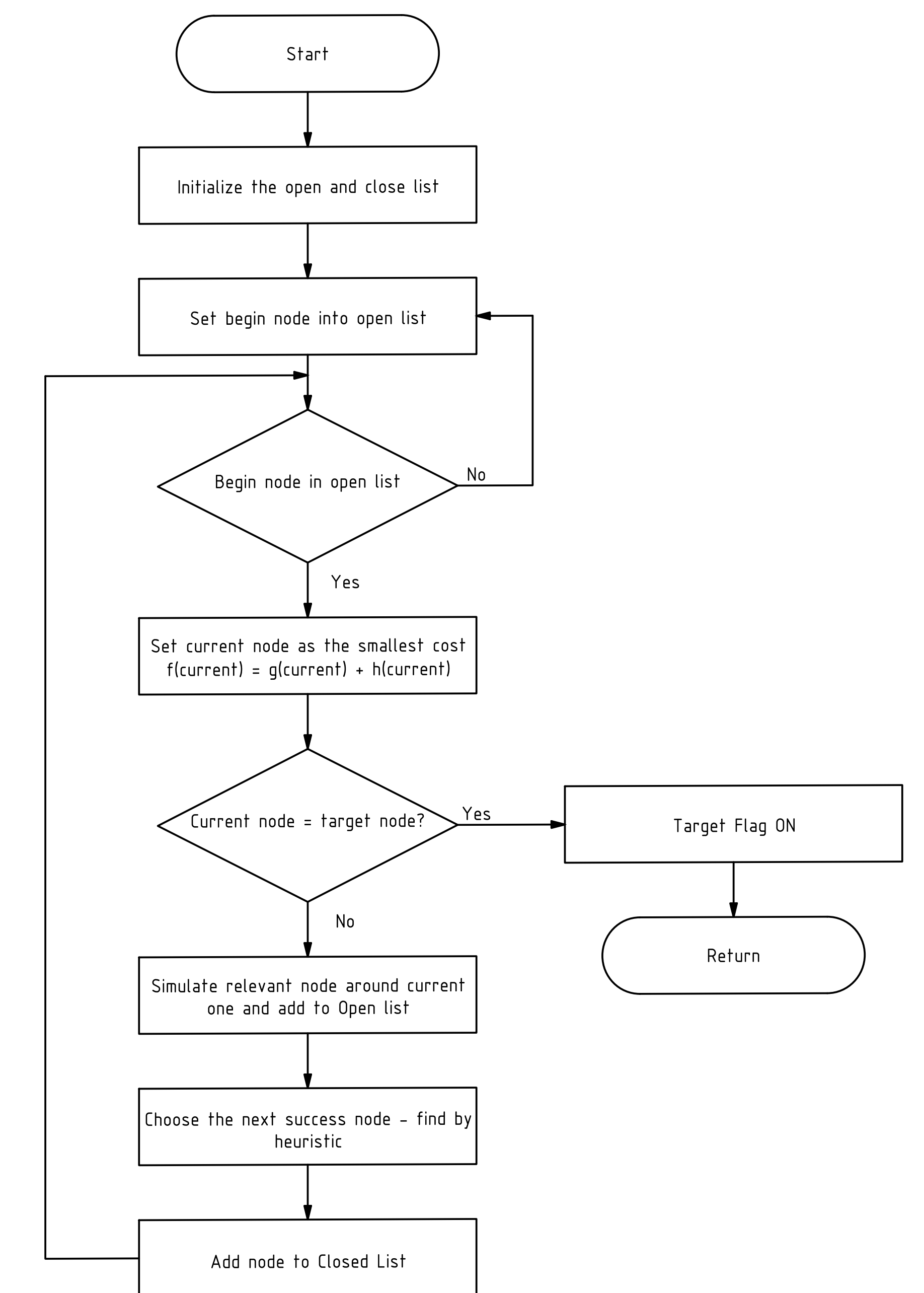
## Main program of MCU



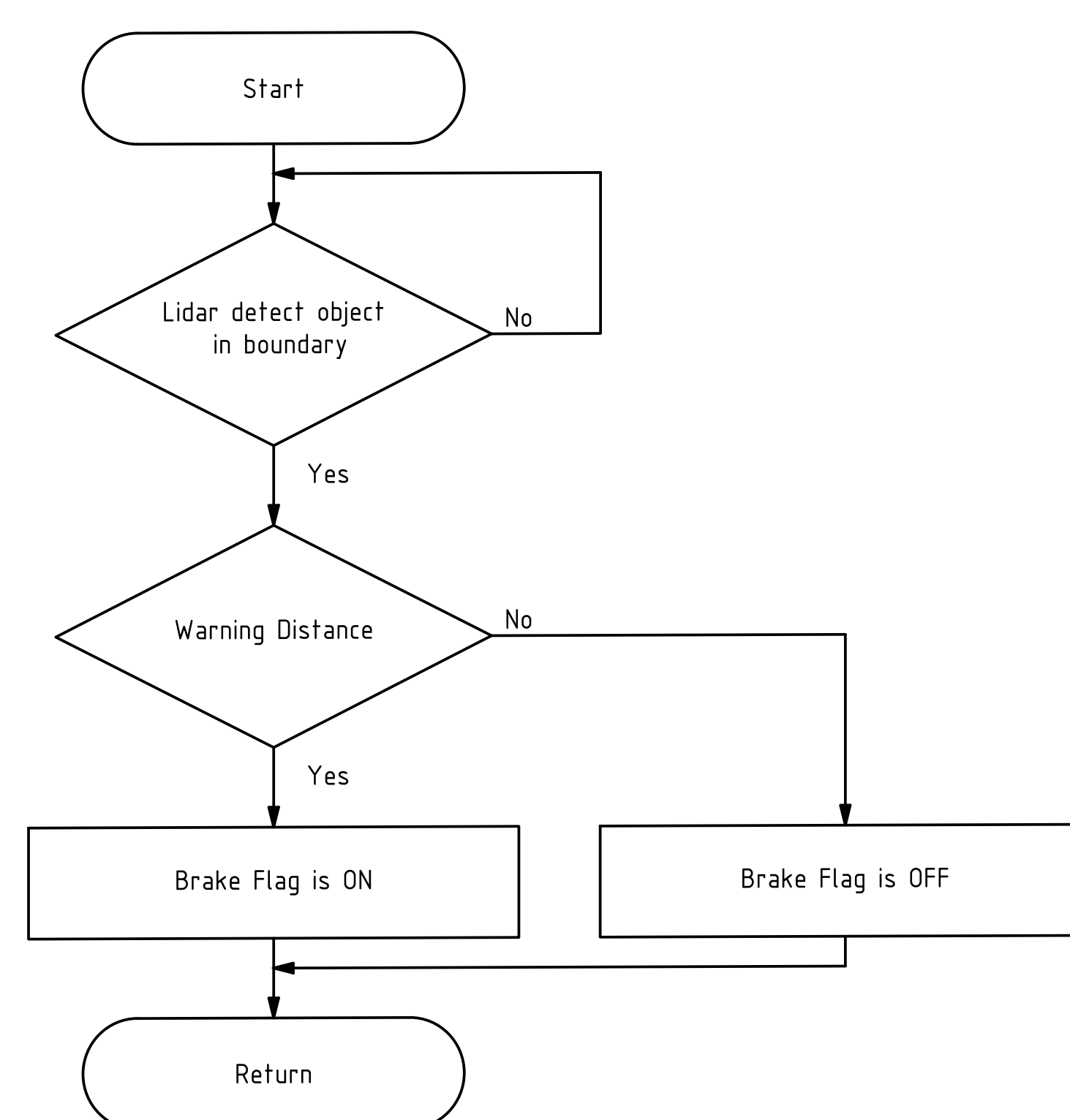
## Map Sever



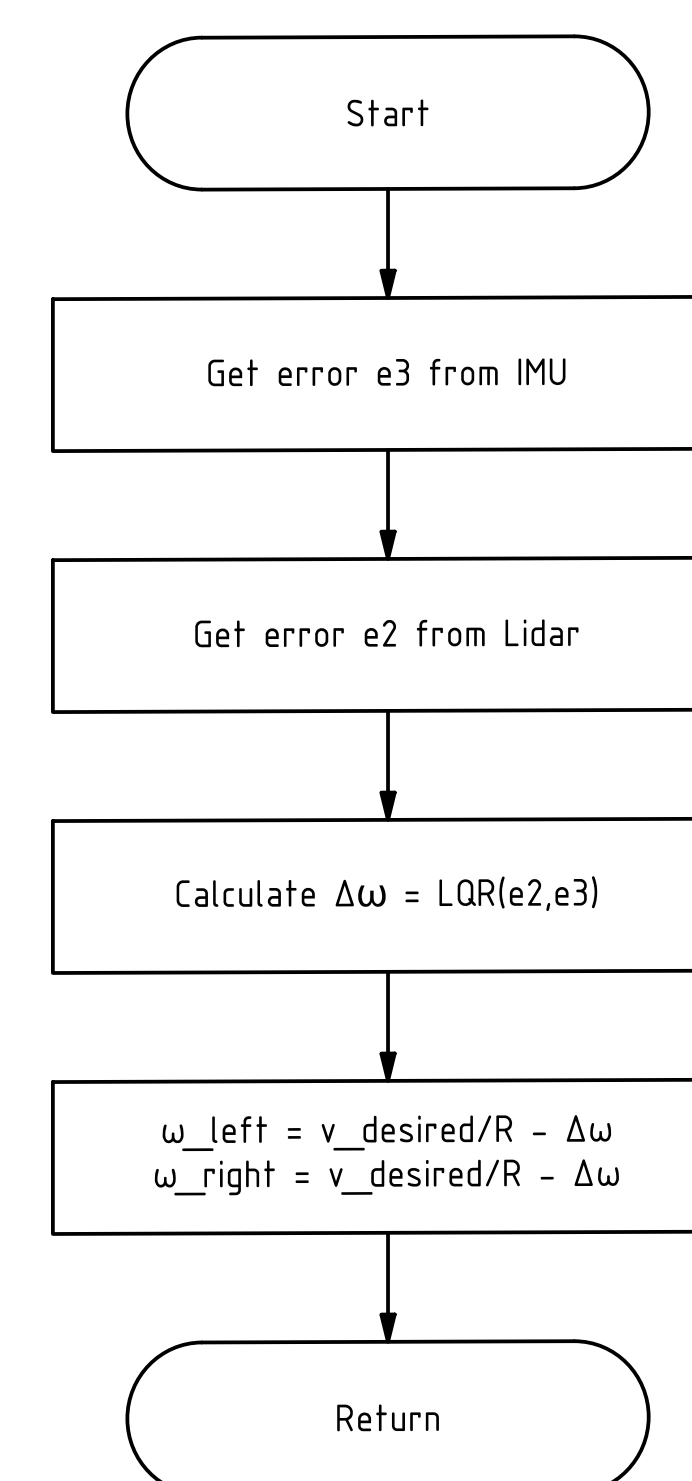
## Global Planner: Dijkstra Algorithm



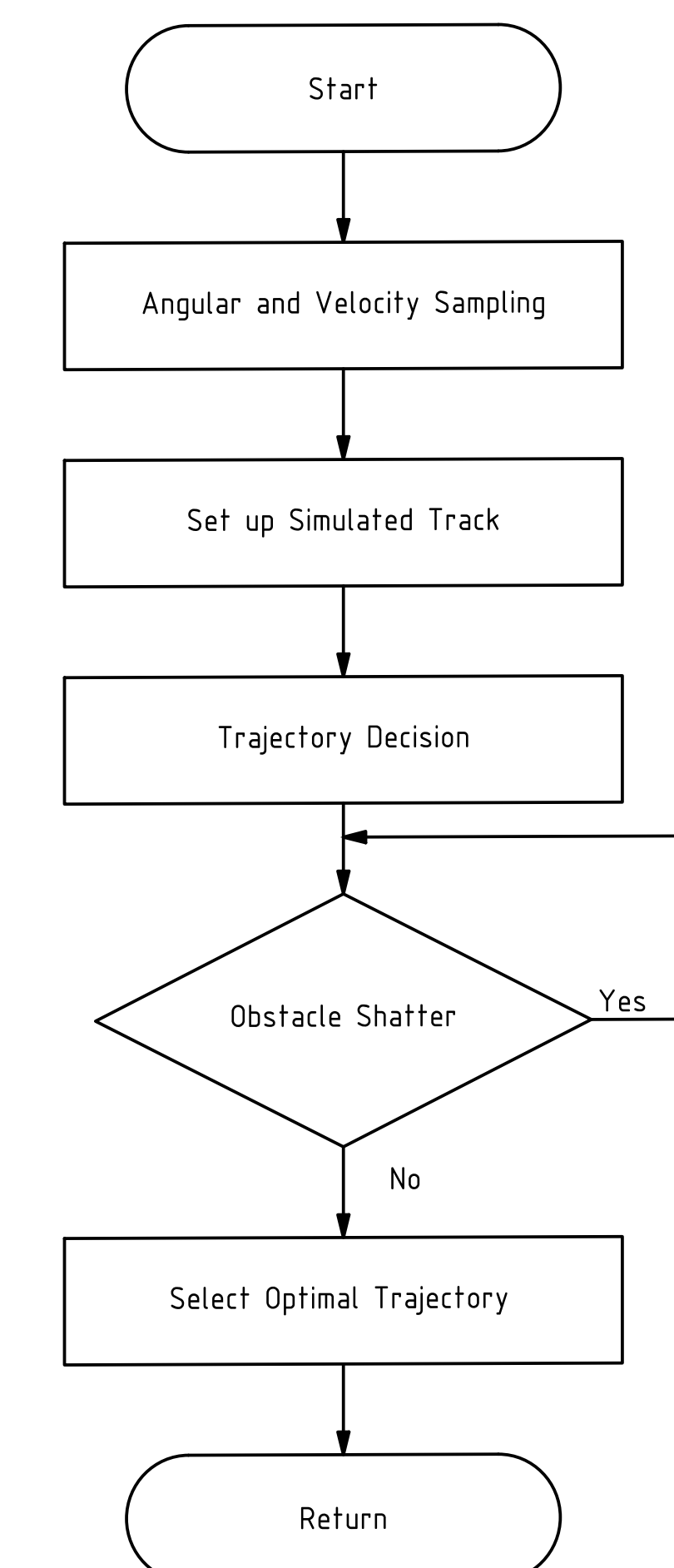
## Global Planner: A\* Algorithm



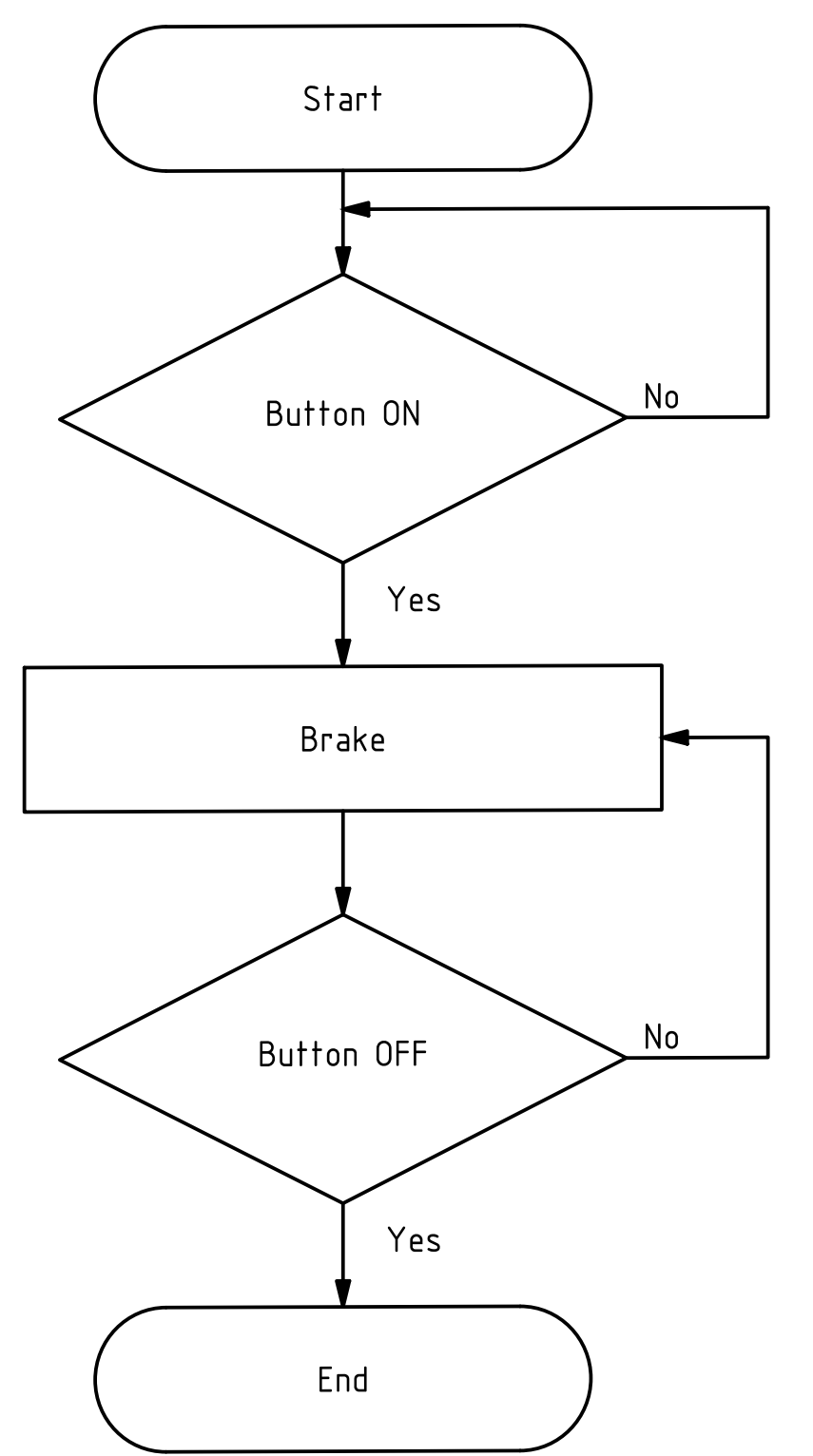
## Dangerous Zone



## Following Trajectory



## Local Planner: DWA Algorithm



## Emergency Stop

*Note:*

v\_desired: the input desired velocity (rpm)  
p\_desired: the input desired position (deg)

$\omega$ : the angular velocity output from LQR (rpm)  
 $\phi_{desired}$ : the input desired orientation (deg)

TOWING AGV					FINAL THESIS		
Function	Name	Signature	Date	ALGORITHM DRAWING	Number	Mass	Scale
Name	Trinh Hieu		8/11		1		
Instructor	Quoc Bao		8/11				
	Le Thanh Hai						
Checked	Name						
					HCMC University of Technology		