* Camera to laptop stable connection
* At the beginning scan whole image
* Map the image to 2d coordinate system



* Red - Obstacles
* Blue - Targets
* Green - Sphero
* Have the objects (classes) saved with coordinates for each nodes/objects
  + Center point
  + Edge point
  + Bool obstacle/target
  + Next coordinates ( predicted with the command for movement)
* Calculate which uninterrupted path is the closest target
* Move towards the target
* On each next state cut the image only around the sphero
* Calculate only those changes
* Update the map
* Control Sphero

Links:

Color