

Filled arrows: as previous flowchart

Dotted arrows: suggestions by me

MIN to deploy
(starting near SCS)

Fly towards
previously deployed
MIN?
or
Fly towards MIN with
the least neighbors?
or
Fly towards...

How to secure
a safe path to
target?

Is MIN close enough
to target MIN?

NO

YES

Receive info from
neighbors "N(i)"

Info from neighbor "j"

Number of neighbors, |N(j)|
Position estimate of MIN j
RSSI wrt. MIN j

Calculate direction of motion

Heading calculation

$$\psi_i = \psi_{N(i)} + \psi_R$$

$$\psi_{N(i)} = \sum_{j=0}^{N(i)-1} \frac{\alpha_j \psi_{ij}}{\alpha_j}$$

$$\alpha_j = \begin{cases} 1, & j \text{ has less than } \kappa \text{ neighbors} \\ 0, & \text{otherwise} \end{cases}$$

ψ_R = random value

Additional
angular term
for obstacle
avoidance

PDF of
 ψ_{i2}
?

Move at constant speed

RSSI from some MINS above
a given threshold?

No

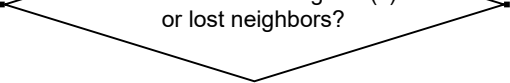
Land

Yes

Yes

No

Discovered new neighbor(s)
or lost neighbors?

A diamond-shaped decision node with a solid black border. It is connected to a dotted line on the left and a dotted line on the right. The text "Discovered new neighbor(s) or lost neighbors?" is centered inside the diamond.