Algorithm outline

1. GPS -> Position of module in absolute space +- GPSerror (John)
2. Angle of motor + RSSI -> Position of module in relative space (Erik)
3. Take the above two and add the position of the access points in absolute space (John)
4. Use this to find the position of the module in absolute space with an error less than GPSerror (John)
5. Send to GUI (somebody) and to RC car (Erik)

Inputs and Outputs to each other’s functional block

John

OUTPUT:

Initial Motor Angle to Erik

Absolute Position Package to Erik

INPUT:

Relative Distance Packages from Erik

Check Position Flag from Abdullah

Erik

OUTPUT:

Relative Distance Package to John

Current & Future Position Package to Abdullah

INPUT:

Absolute Position Package from John

Abdullah

OUTPUT:

Check Position Flag to John

INPUT:

Current & Future Position Package from Erik