

robot.py

```
def get_path(start, end):  
    return make_plan(start, end)
```

```
def follow_path(robot, path):  
    for point in path:  
        robot.move_to(point)
```

```
class Robot:  
    def send_speed(self, v, w):  
        serial.write(v)  
        serial.write(w)
```

# Algorithm