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Autonomy and Human/Operator Interface Needed for Competition

**Autonomy**

The system will use a reflexive control scheme due to its fast reaction speeds and the environment in which it will be operating in is unknown. The system will use Dijkstra’s algorithm that will be constantly updating the path it will be following as data is collected from the camera and Lidar.

**Human/Operator Interface**

Once the vehicle begins traversing the obstacle course, it can accept no human input other than the wireless or mechanical e-stop button. A simple GUI will be created that will begin autonomous traversal of the obstacle course on input from the operator.