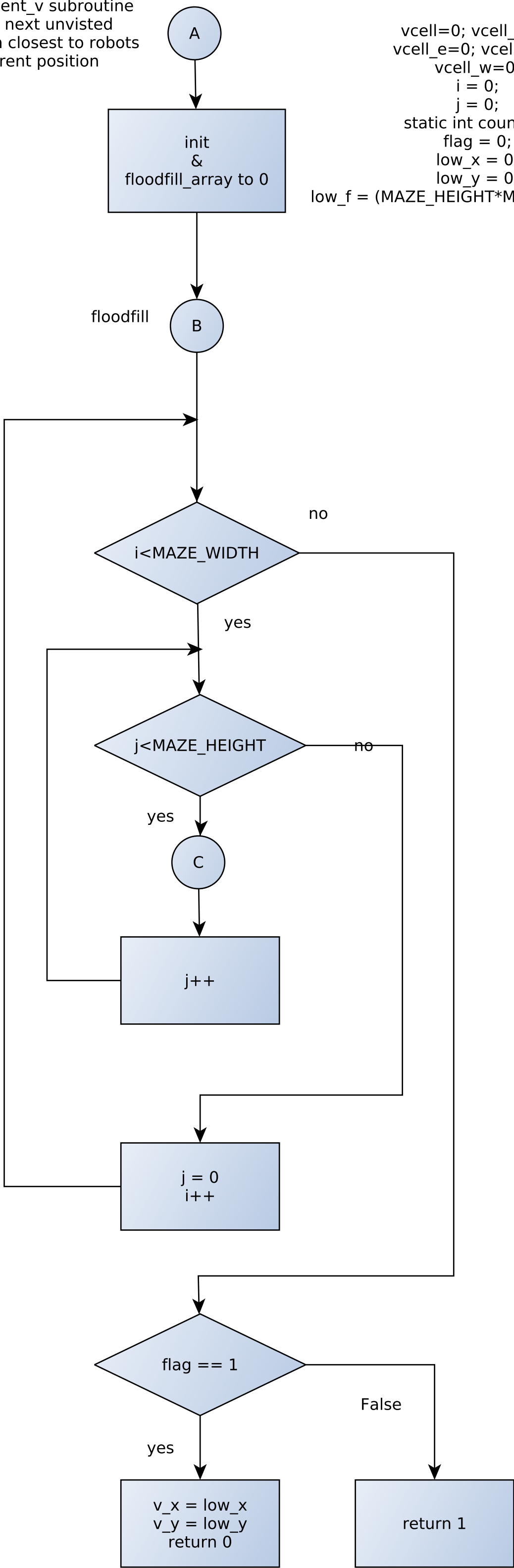


increment_v subroutine
finds next unvisited
location closest to robots
current position



vcell=0; vcell_n=0;
vcell_e=0; vcell_s=0;
vcell_w=0;
i = 0;
j = 0;
static int count=0;
flag = 0;
low_x = 0;
low_y = 0;
low_f = (MAZE_HEIGHT*MAZE_WIDTH)+1;

