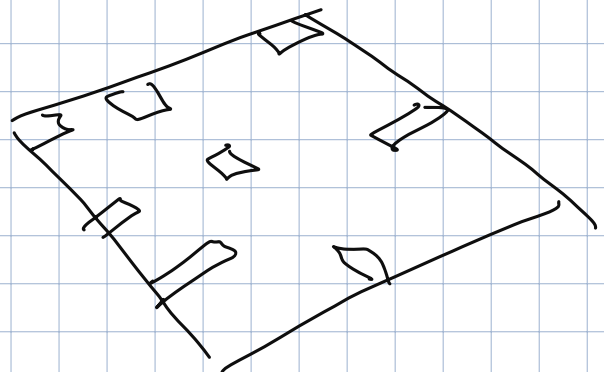
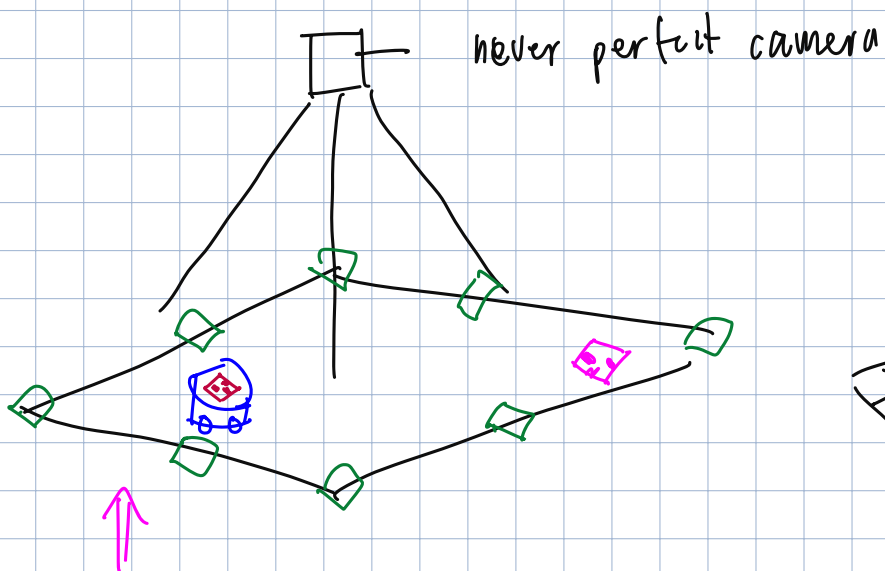
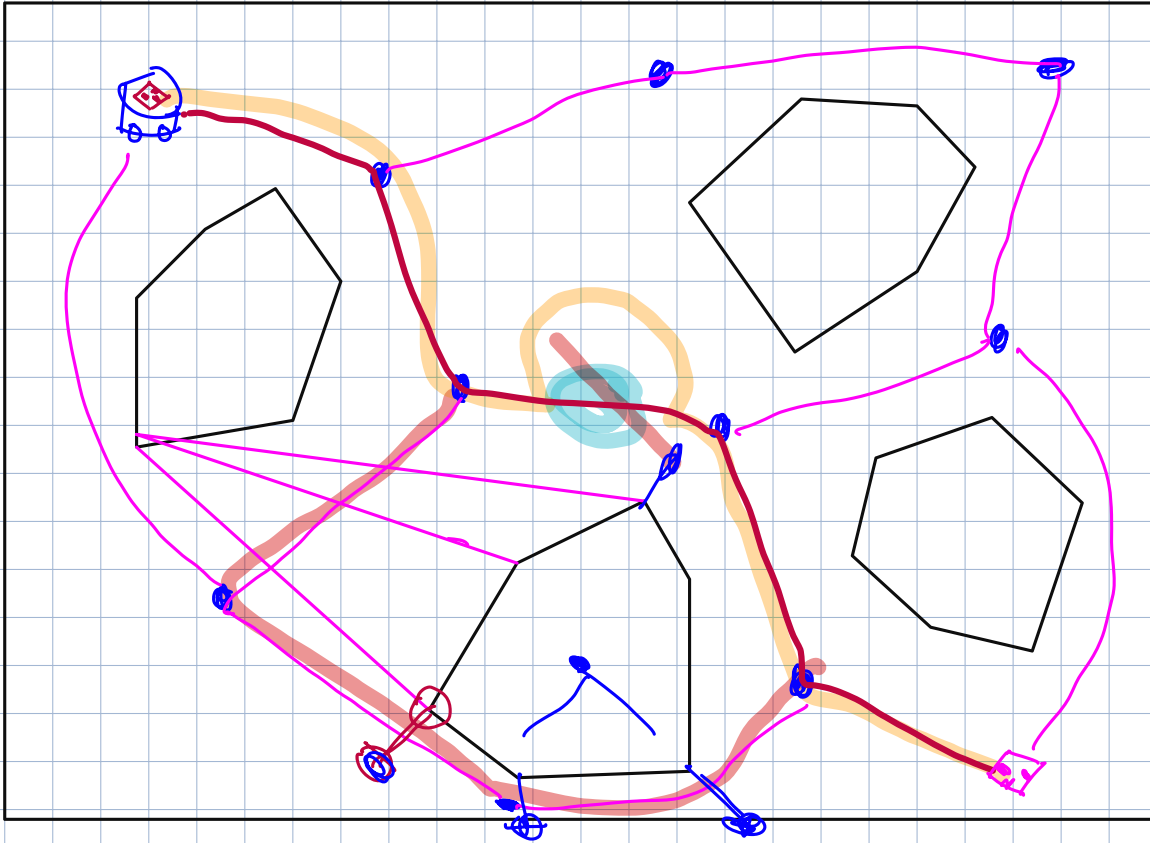
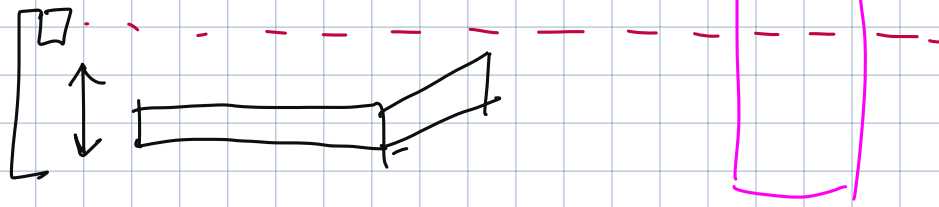


→ Which implement easiest vs hardest



→ Aruco codes

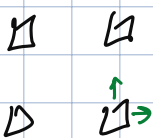
3D print



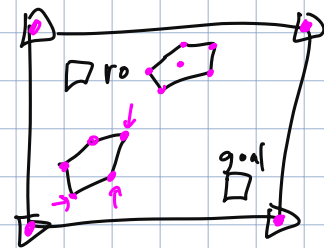
envtl
potential
field

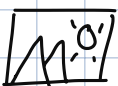
put \rightarrow feedback loop \leftrightarrow through vision?

put map on robot ? \rightarrow PC

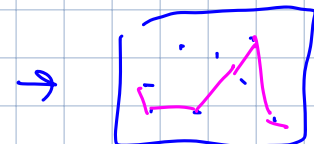
① vision 


[]



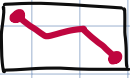
② pre process 

[all nodes]




③ Graph 

[best path]

(4) Path finding  → Nodes list $[(0;0), (4;5), \dots]$

↓ To Thymio

(7) Filter position (Pos estimation)  ← Motor commands

(6) ↑ ↓ Prox detect
(8) Potential field