

- Extra
- (1) change of mind
 - (2) button to request nav - rerun
 - (3) on/off

```
while(1)
{
  THRD_NAV
  → pedometer
  → process-map
  → IMU
  → camera
}
```

```
main
• process map
→ process map
```

→ ask user

```
while(1)
{
  // taking
  sonar
  input
  // give speaker
  when obstacle
  // flag
}
```

NAV

Rerun A* search

- (1) when u think you reached destination, but haven't.
- (2) when person goes wrong way.

```
// get current location, cur-dist
// camera → microphone, button
```

```
while(1)
```

(*)

```
// run A* search
while (direction == TRUE-DIR
and dest not reached)
```

// count steps, IMU

- (1) count-steps
- (2) check direction

//

}

OBS

```
while(1)
```

```
{
```

```
// sensor input (sonar)
```

```
if (too-close)
```

```
{ // kill NAV-THREAD
```

```
// speaker = You are bumpy;
```

```
// speaker speaker = please press button;
```

```
// wait on button-press
```

```
// restart NAV-THR with map as arg
```

```
}
```

```
}
```

```
}
```

```
// trigger camera = red room
if (reached dest?)
```

```
{ → turn camera off
```

```
// speaker = you have reached
= turn off glass
```

```
else {
```

```
// use QR code to know room
```

```
// current-location = new-room;
```

```
(*) // IF WORST, tell USER to ask around
```