Main()

Initialize

Compute shortest path

Check robot's position

Check goal

Not arrived

Arrived

Move along with shortest path

Detect edge changes

Decide whether to update

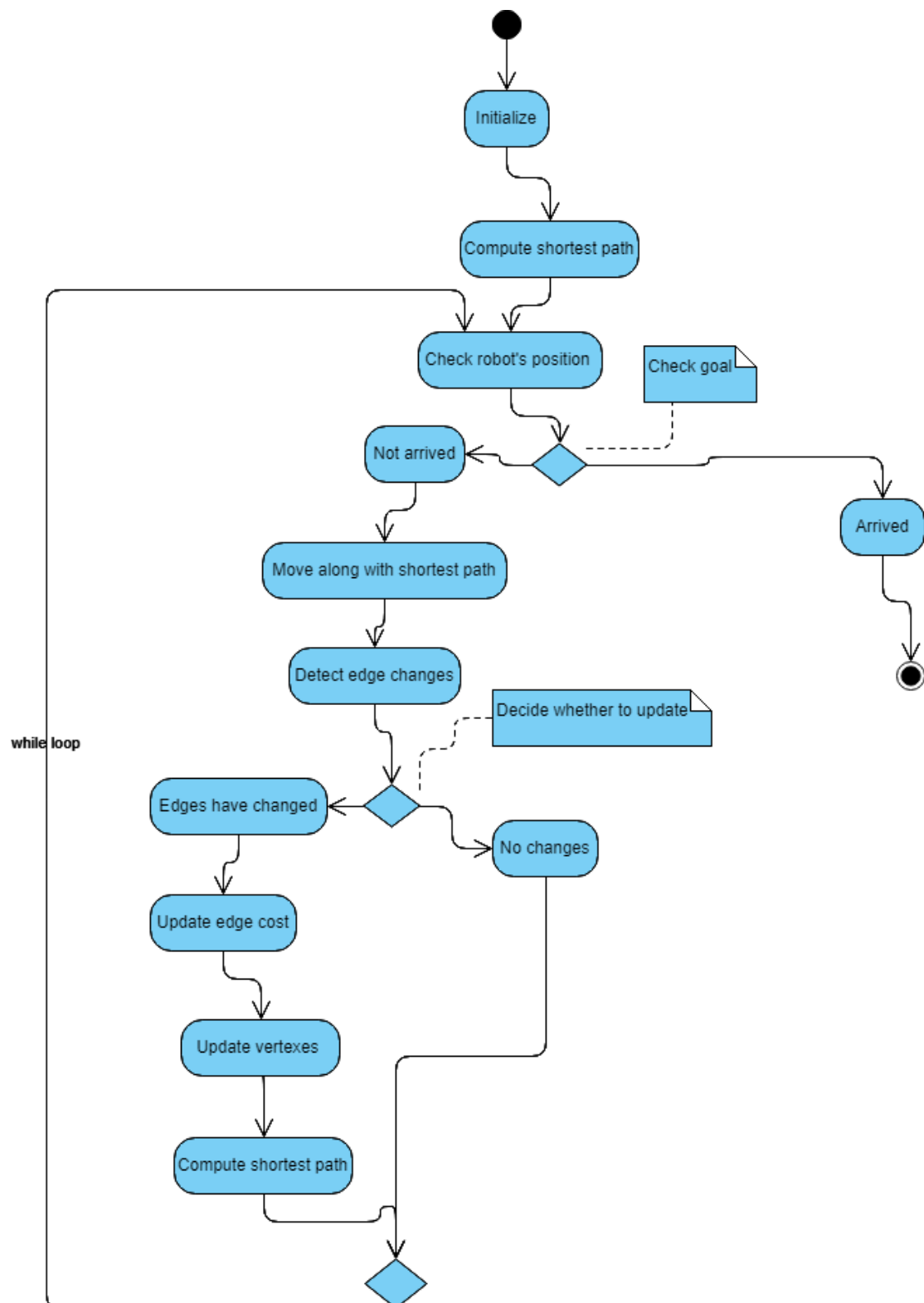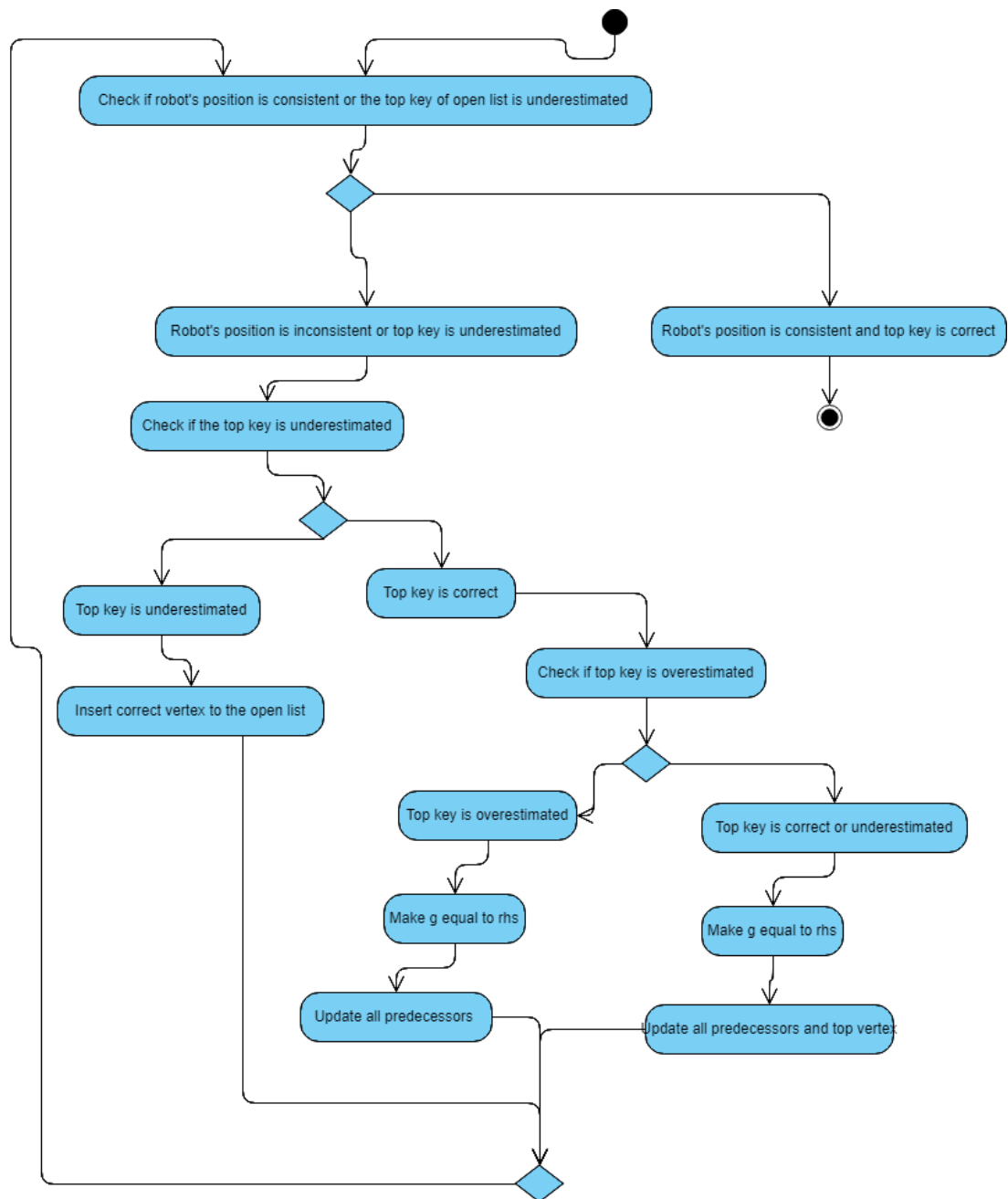Edges have changed

No changes

Update edge cost

Update vertexes

Compute shortest path

while loop

computeShortestPath()

updateVertex()

Check the vertex is the goal or not

Not the goal

Is the goal

Update the rhs value

Remove vertex from open list

Check if the vertex is in open list

In open list

Not in open list

Delete the vertex in open list

Compare g value and rhs value

Vertex is consist

[g == rhs]

[g != rhs]

Vertex is not consist

Insert updated vertex in open list