Project Midterm

Trajectory Generation and Following with Position Correction

Team: Crash Pilots

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Given a graph $G=(V,E)$, where $V$ is the set of markers connected via edges $E$ generate a feasible trajectory from a given start point to an end point.
Status

Demonstration
What’s next

1. **Test and configure trajectory control**
   - Adjust gains
   - Evaluate WIFI delay

2. **Merge trajectory control with landmark detection**
   - Retrieve waypoints according to marker position
   - Plan path on graph

3. **Allow interactive selection of target position with autonomous planning**