Last class: building your executable
- make utility
  - Ant (Apache)

System dependent

limits in time & space

1. codecon.bloomberg.com

2. login with gmail or twitter
   codecon
   (new)

3. link this to your libemail
   buffalo.edu
   click on email on login left.

4. courses → CSE 321
http://www.cse.buffalo.edu/~bina/cse113/
fall 2015
point A. 

Post office

\[\text{Shortest path} \quad \begin{pmatrix} 10, \ 20 \end{pmatrix} \]

+10

+20

Point

B

Coordinates

\[\begin{pmatrix} x_B, \ y_B \end{pmatrix} \quad (20, \ 40)\]

level 0: 1 drone

level 1: \(\frac{3}{2}\) drones

(no obstacles, no collision)

"struct" 

what are the "data" I need in the "drone" object:

1 drone

level 0-2: avoid static obstacles

level 1-2: multiple drones avoid static obstacles

level 2-2: multiple drone

dynamic locations for collision detection + avoidance
Manhattan distance: $N \rightarrow NE \rightarrow E$

- drone "strict" quadrotor currLoc
- point A
- point B
- table/grid static obstacles
- update dynamic stage obstacles

Design process involves:

Data structures
- my data drone
- static table for immovable objects
- dynamic table/grid for moving objects

Algorithms
- 1. normal path: MD
- 2. static obstacles: MDSO
- 3. other drones: MDMO-v.1
  (assumption) 
- MDMO-v.2