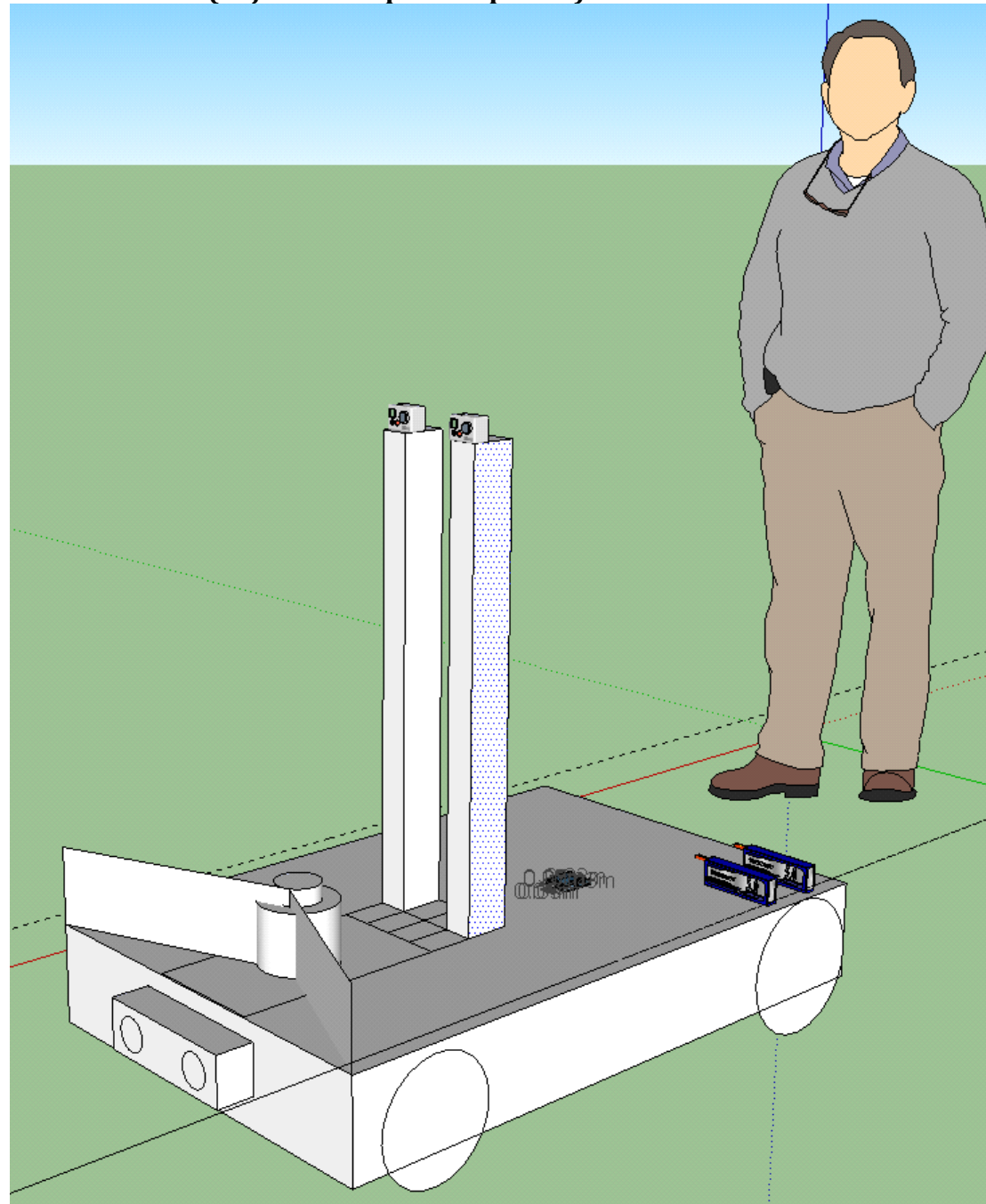


Proximity/Detection Sensors (at front)
Mobile Processor (Arduino or EZ) (behind two pillars)
2D Lidar (a circular object at front)
AGV power source (batteries at the back)
Stereo Camera (objects on top of the pillars)



Shown in the figure is a rough design build of the low cost autonomous mapping and navigation platform. Please note that components or the hull dimensions are not to scale.