FIG. 1

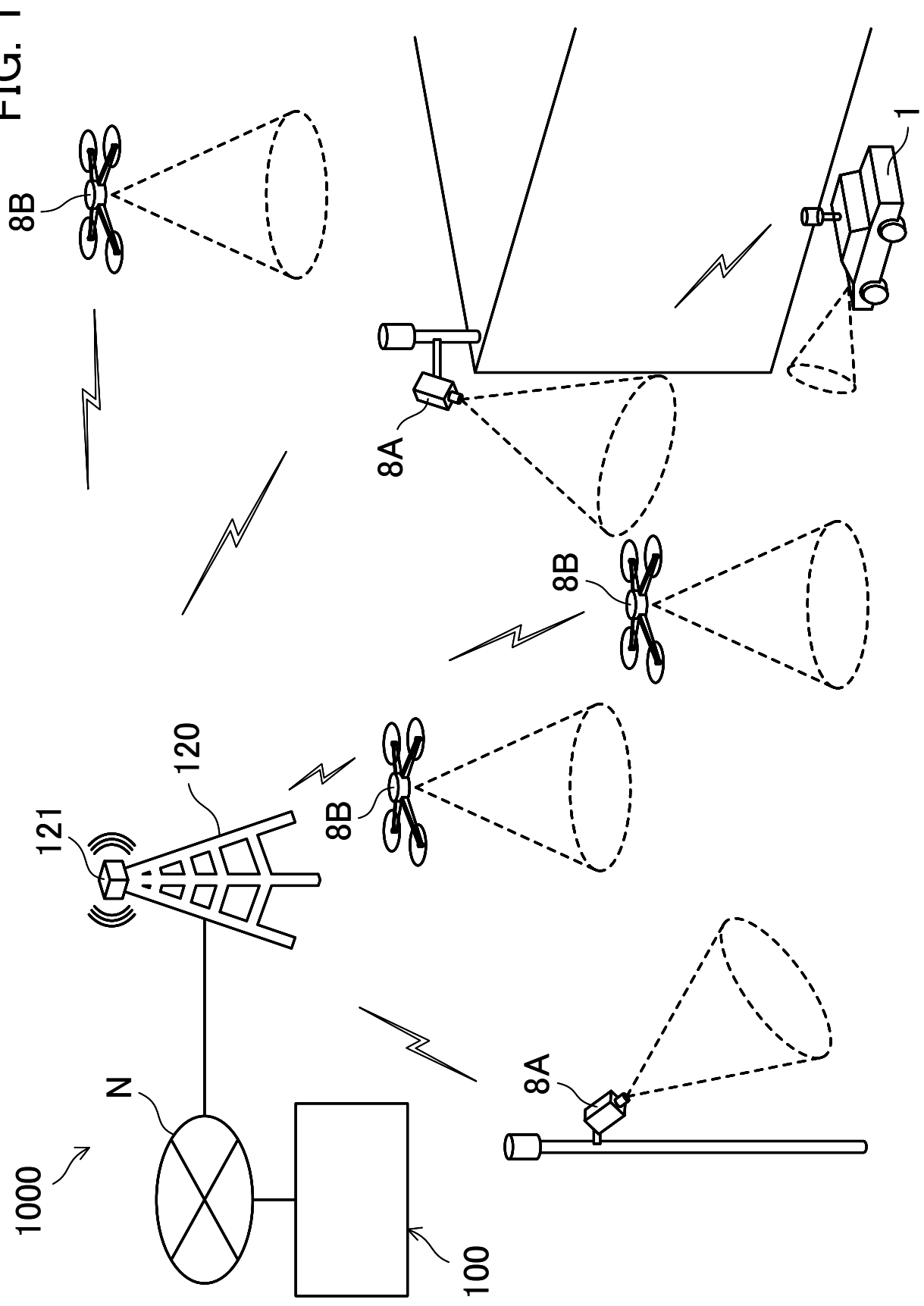


FIG. 2

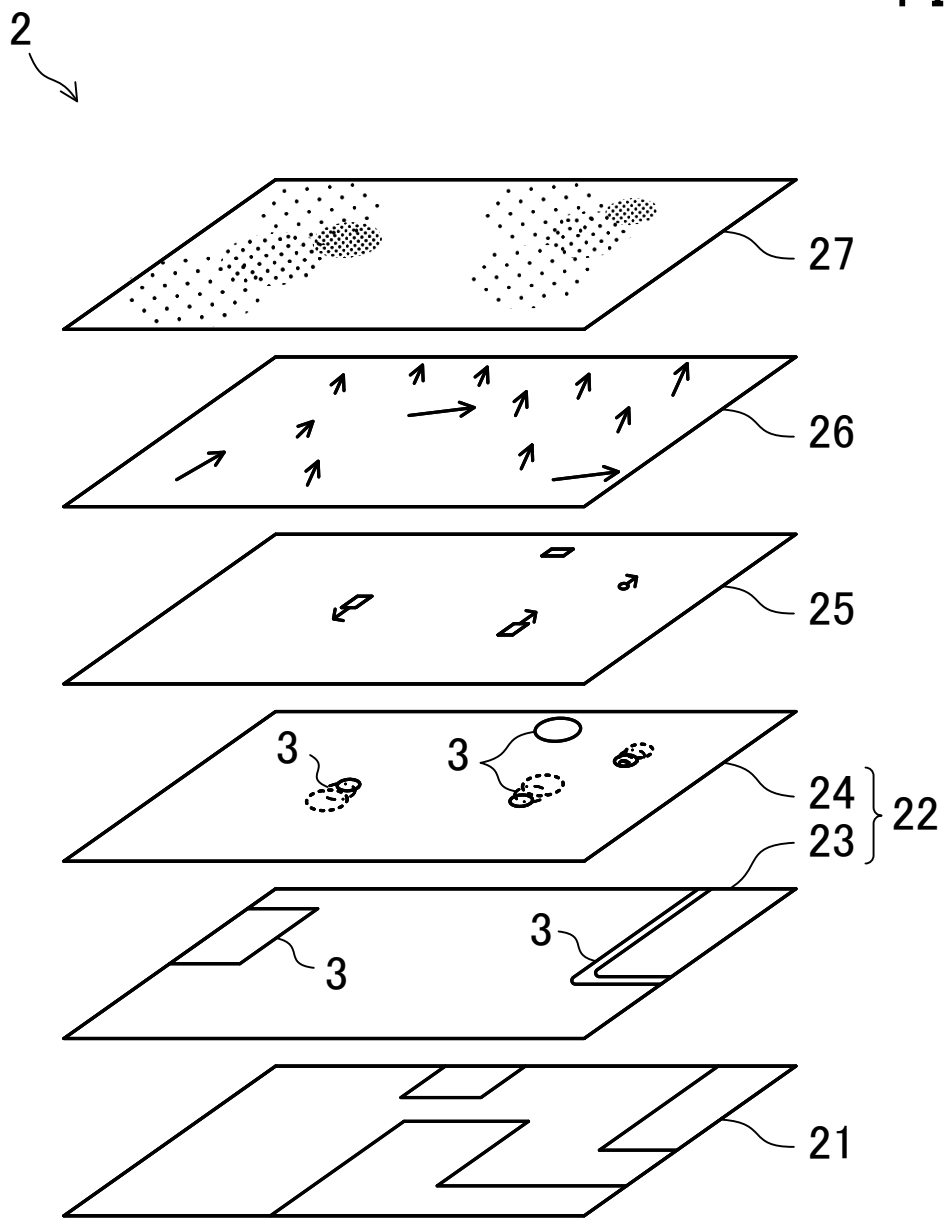


FIG. 3

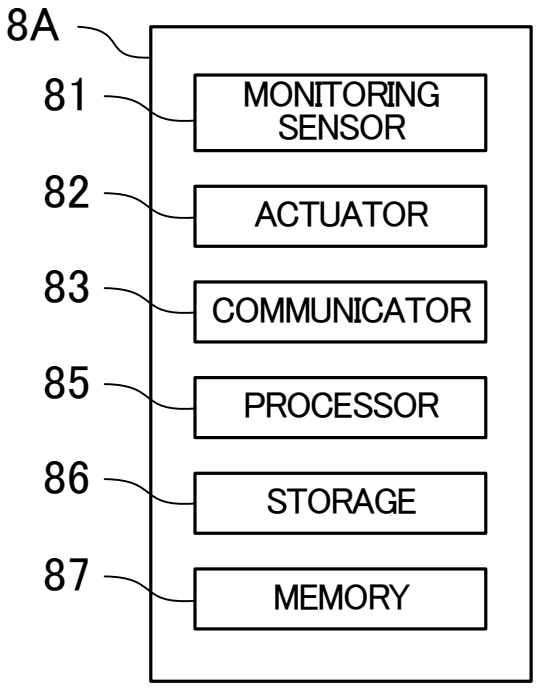

8A
81
MONITORING SENSOR
82
ACTUATOR
83
COMMUNICATOR
85
PROCESSOR
86
STORAGE
87
MEMORY

FIG. 4

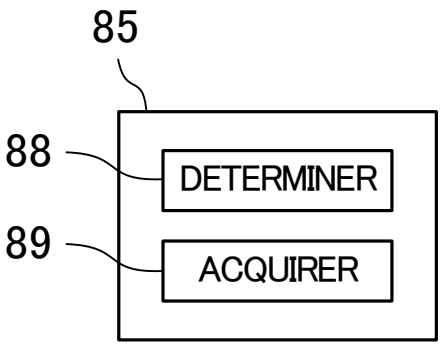

85
88
DETERMINER
89
ACQUIRER

FIG. 5

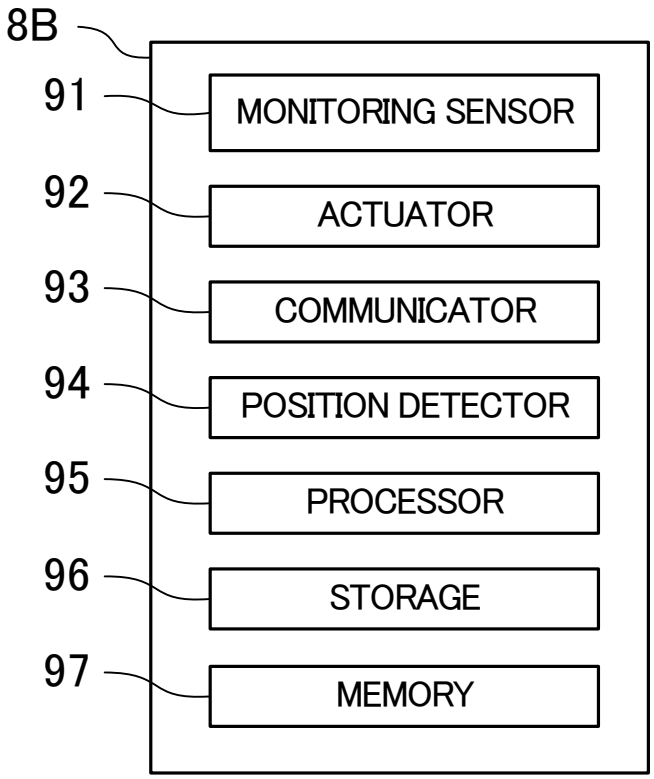

8B
91
MONITORING SENSOR
92
ACTUATOR
93
COMMUNICATOR
94
POSITION DETECTOR
95
PROCESSOR
96
STORAGE
97
MEMORY

FIG. 6

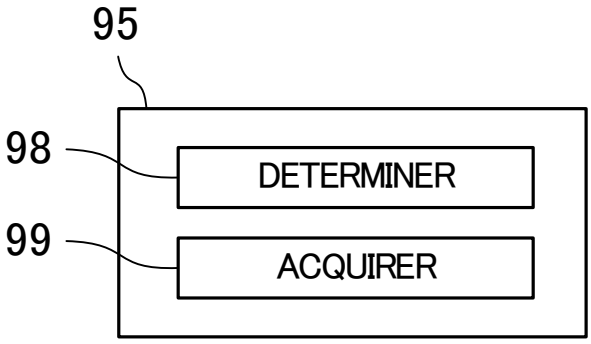

95
98
DETERMINER
99
ACQUIRER

FIG. 7

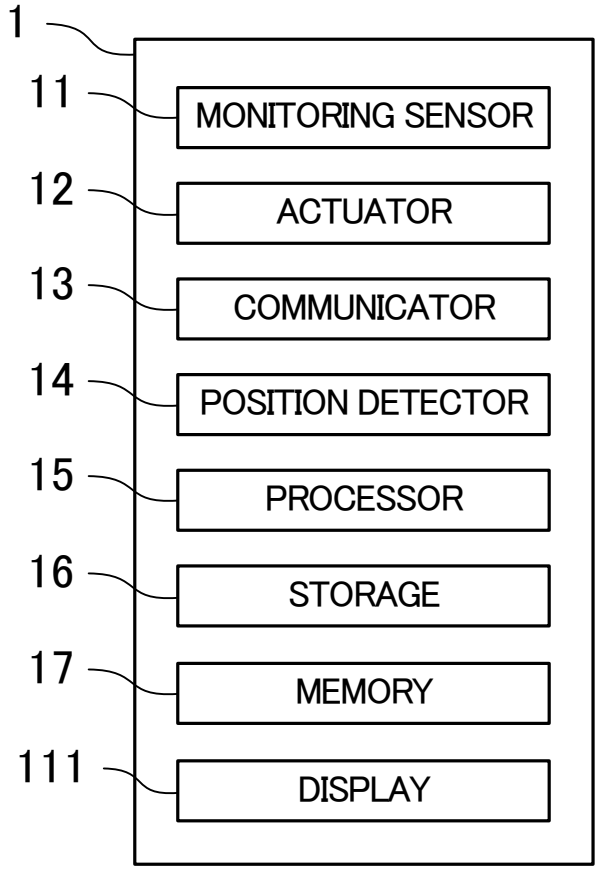

1
11
MONITORING SENSOR
12
ACTUATOR
13
COMMUNICATOR
14
POSITION DETECTOR
15
PROCESSOR
16
STORAGE
17
MEMORY
111
DISPLAY

FIG. 8

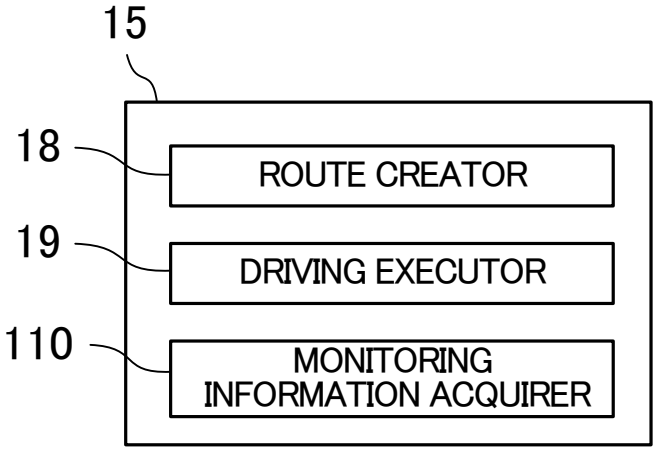

15
18
ROUTE CREATOR
19
DRIVING EXECUTOR
110
MONITORING INFORMATION ACQUIRER

FIG. 9

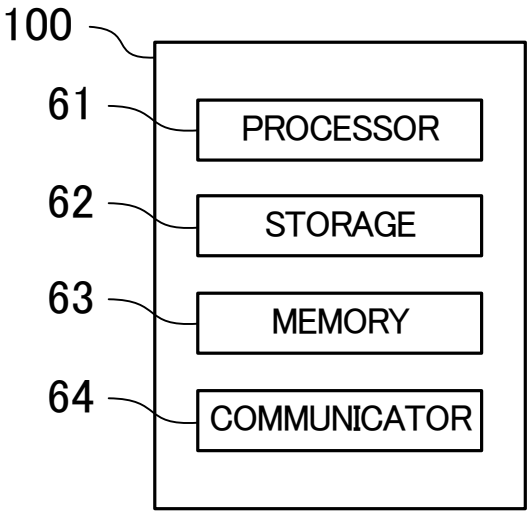

100
61
PROCESSOR
62
STORAGE
63
MEMORY
64
COMMUNICATOR

FIG. 10

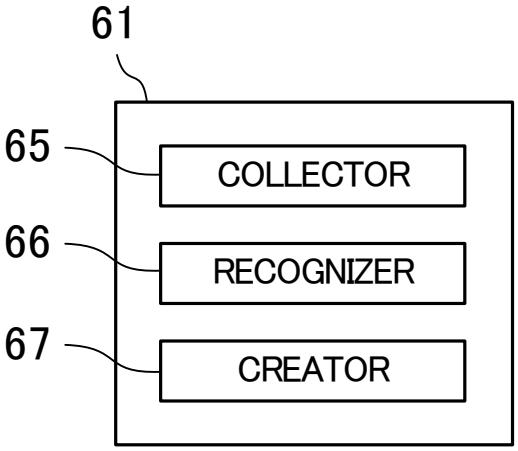

61
65
COLLECTOR
66
RECOGNIZER
67
CREATOR

FIG. 11

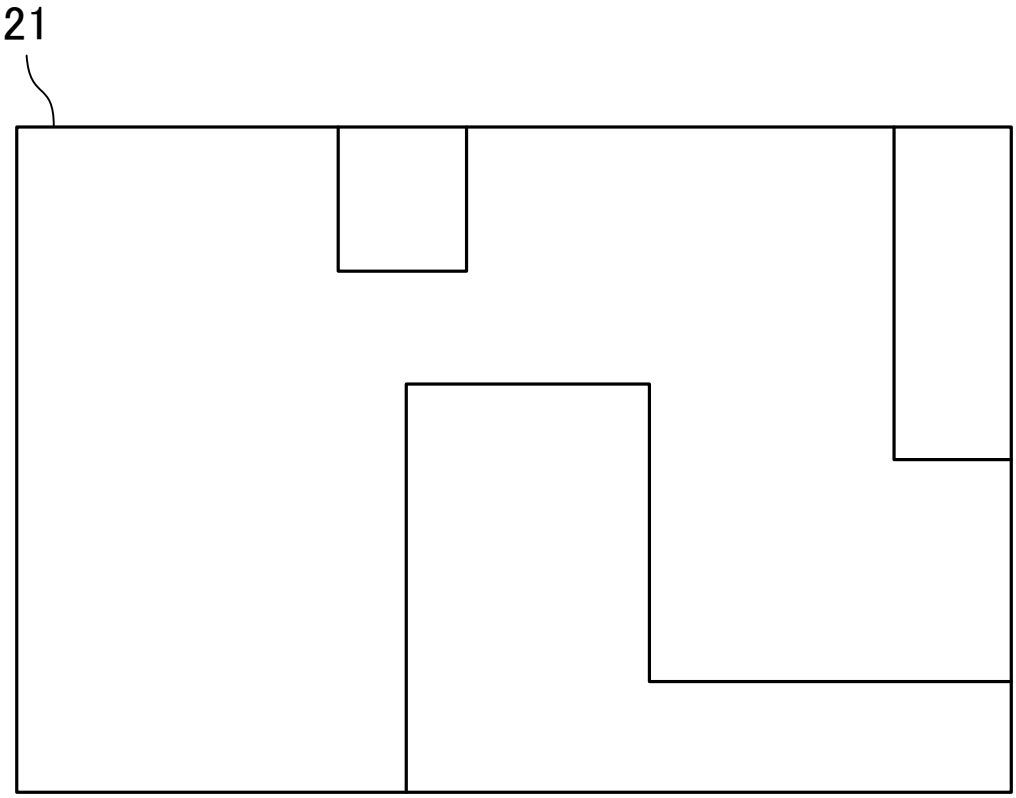


FIG. 12

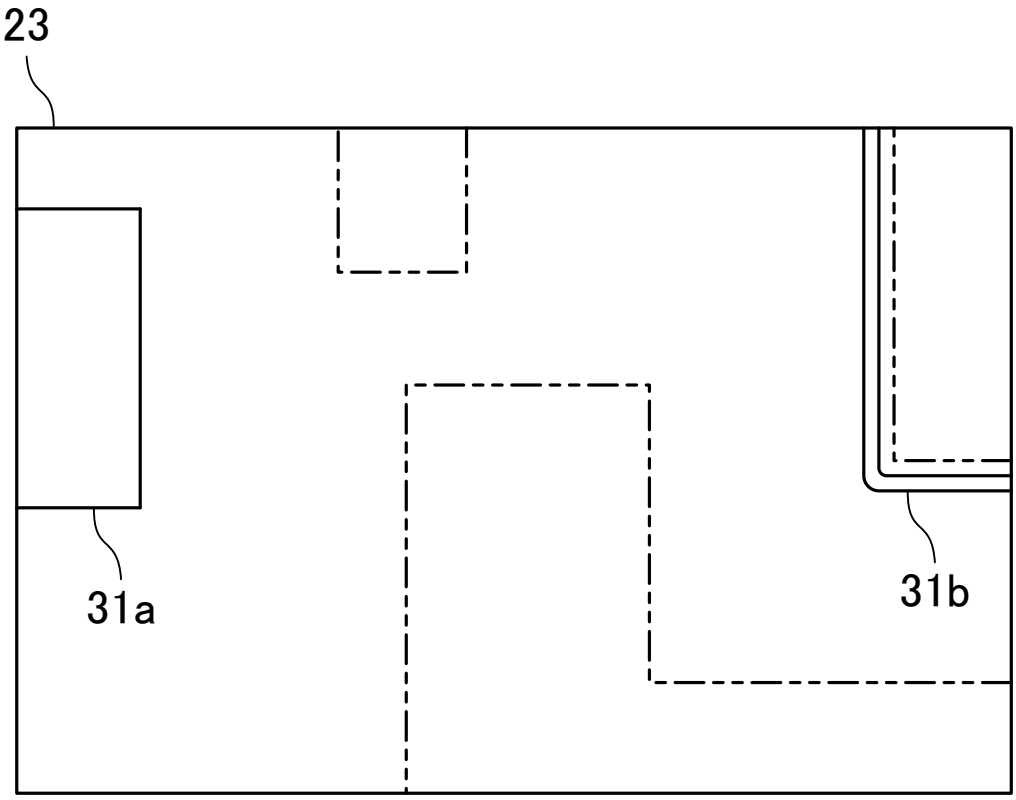


FIG. 13

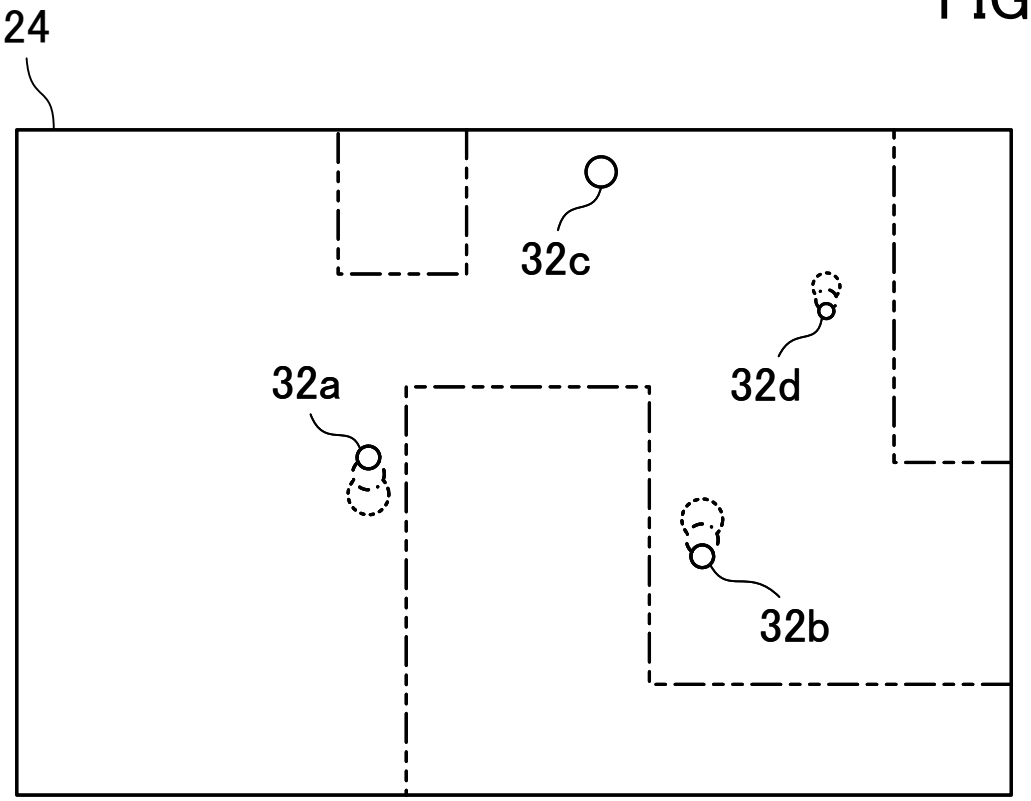


FIG. 14

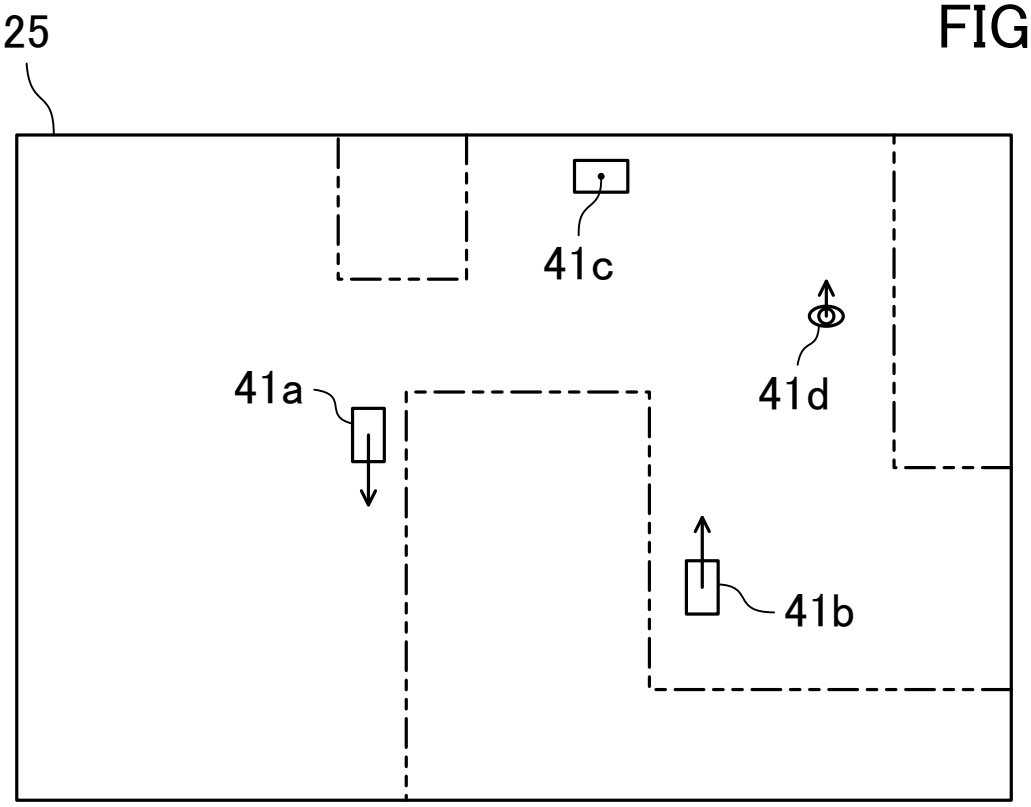


FIG. 15

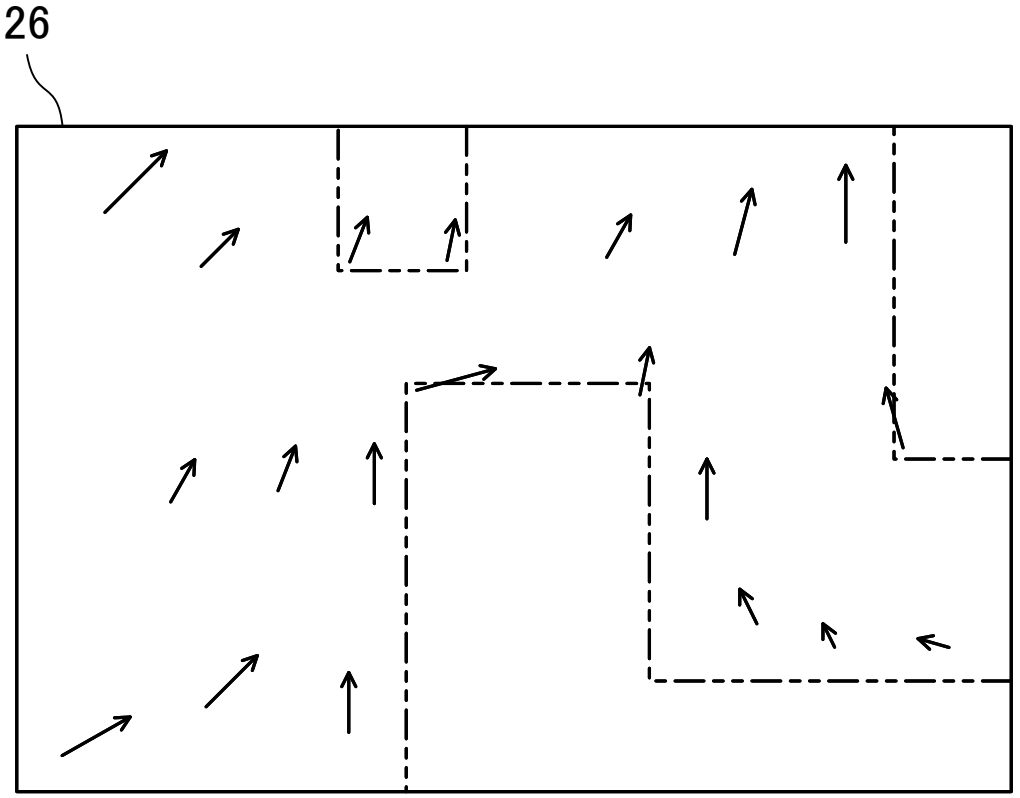


FIG. 16

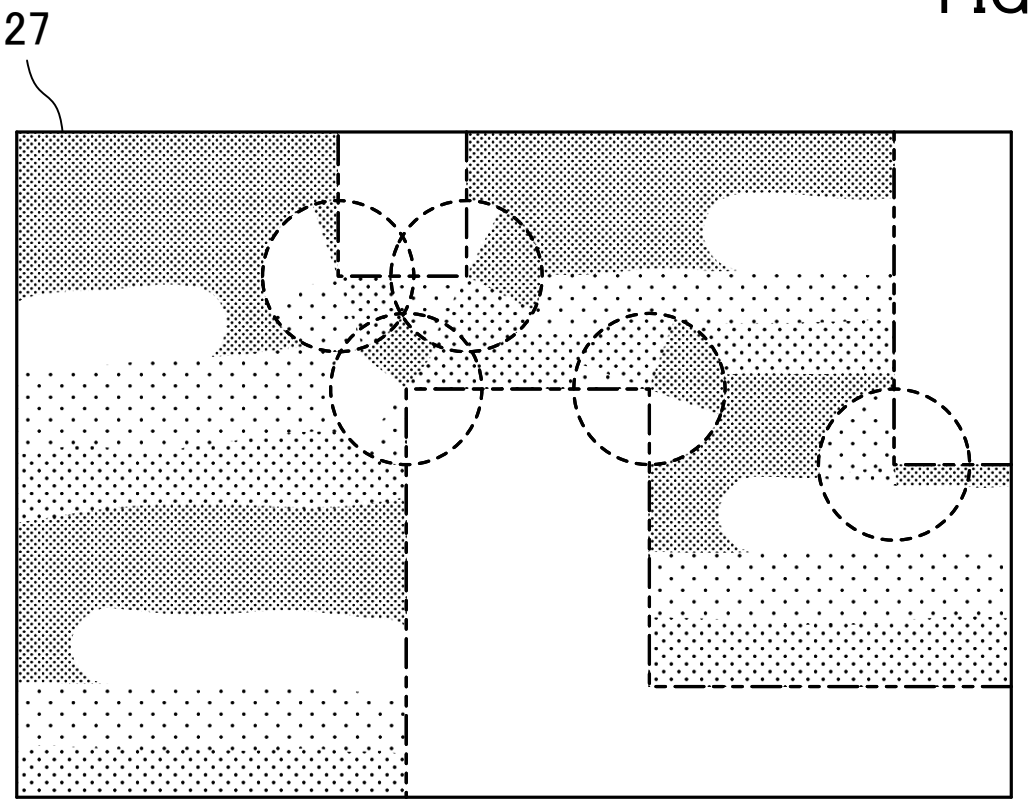


FIG. 17

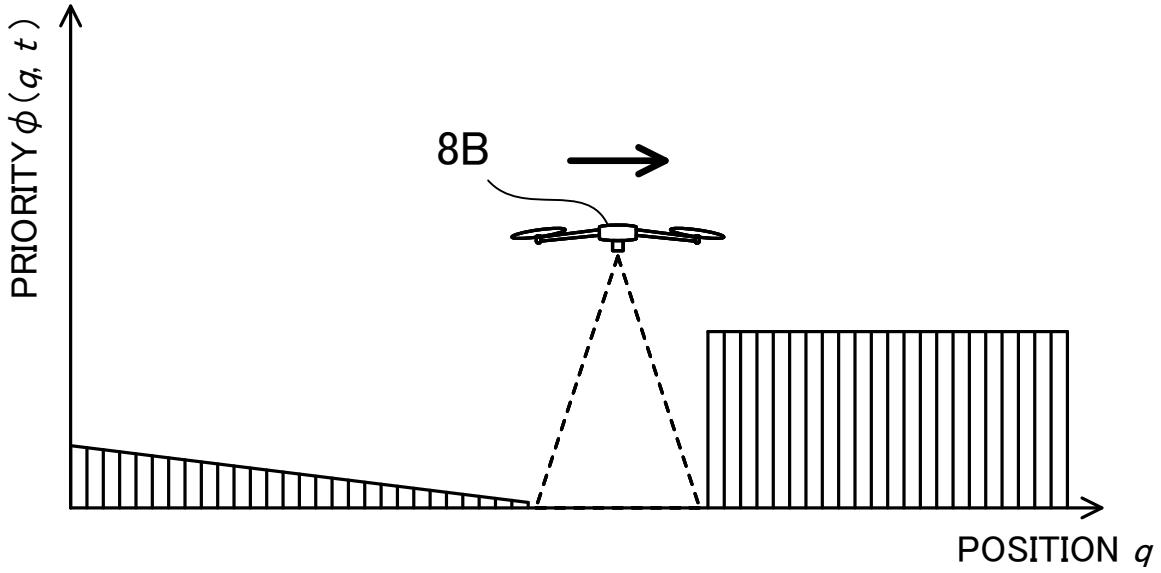

PRIORITY $\phi(q, t)$
8B
POSITION q

FIG. 18

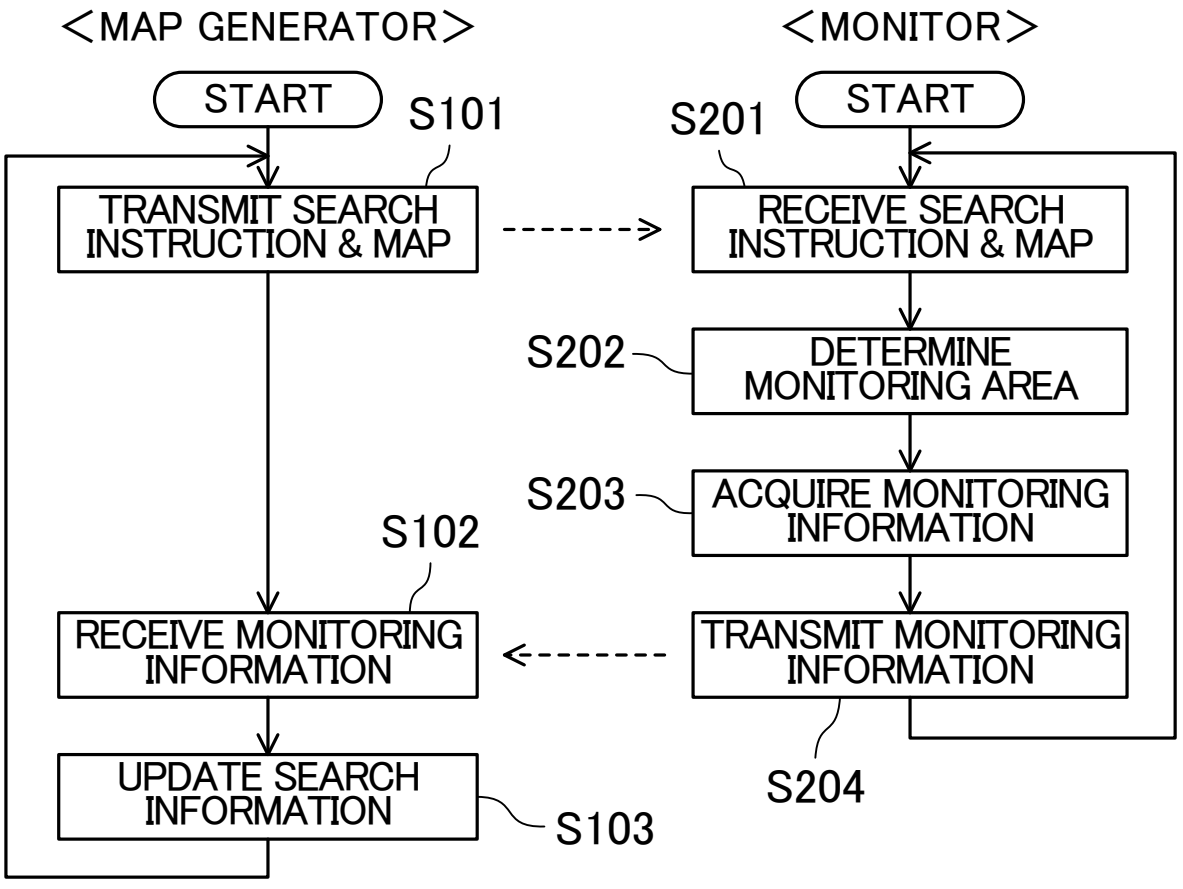

<MAP GENERATOR>
START
S101
TRANSMIT SEARCH INSTRUCTION & MAP
S102
RECEIVE MONITORING INFORMATION
UPDATE SEARCH INFORMATION
S103
<MONITOR>
START
S201
RECEIVE SEARCH INSTRUCTION & MAP
S202
DETERMINE MONITORING AREA
S203
ACQUIRE MONITORING INFORMATION
TRANSMIT MONITORING INFORMATION
S204

FIG. 19

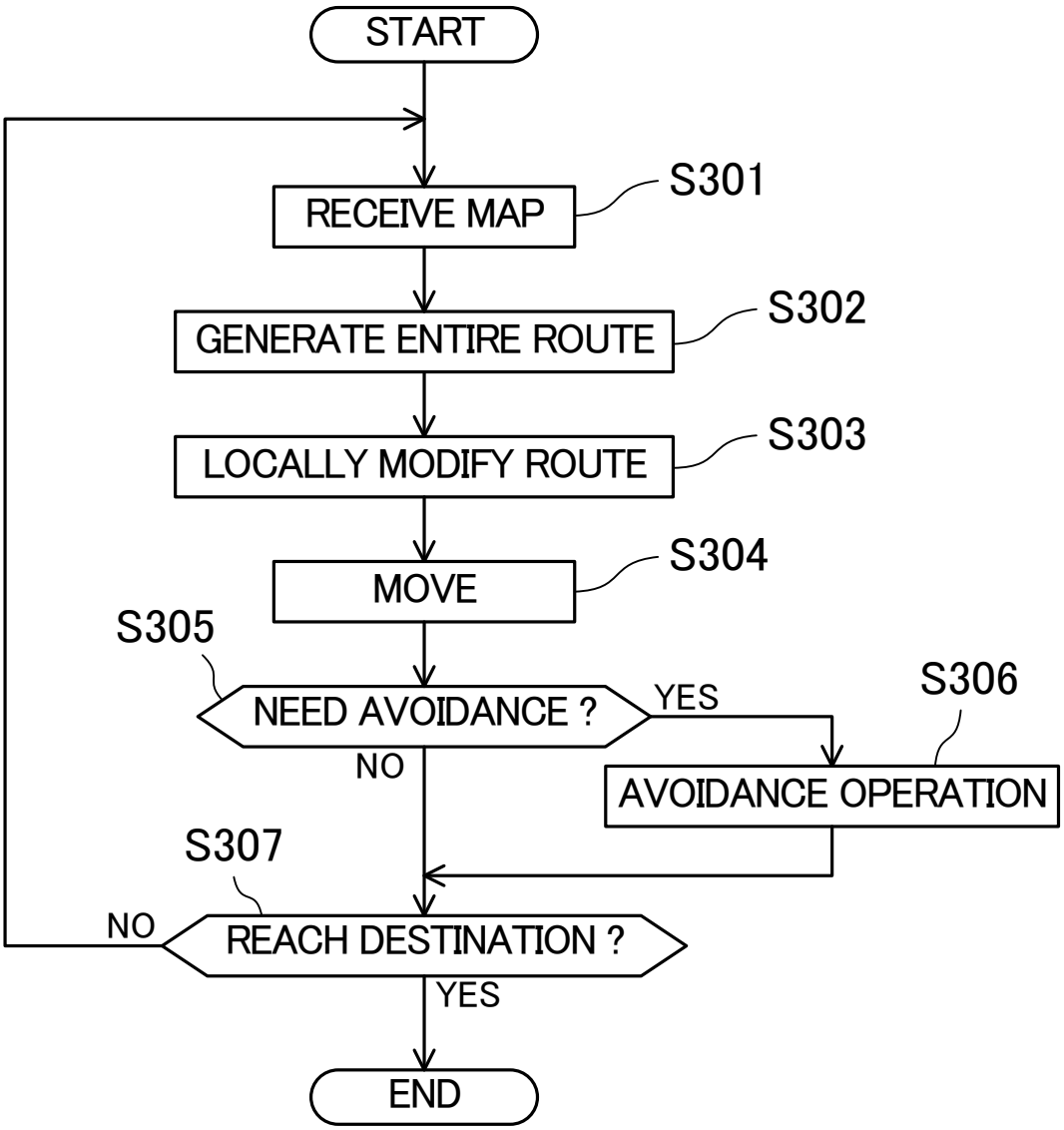

START
RECEIVE MAP
S301
GENERATE ENTIRE ROUTE
S302
LOCALLY MODIFY ROUTE
S303
MOVE
S304
S305
NEED AVOIDANCE ?
YES
S306
NO
AVOIDANCE OPERATION
S307
NO
REACH DESTINATION ?
YES
END

FIG. 20

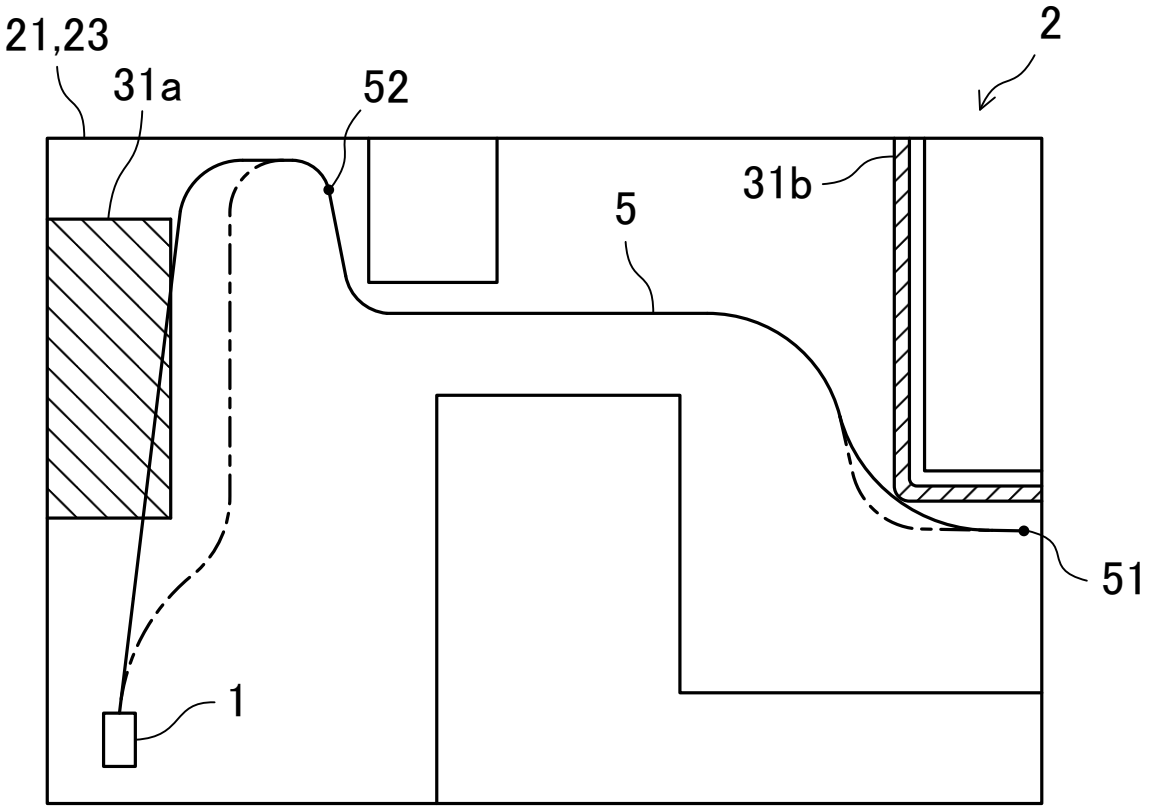

21,23
31a
52
2
31b
5
51
1

FIG. 21

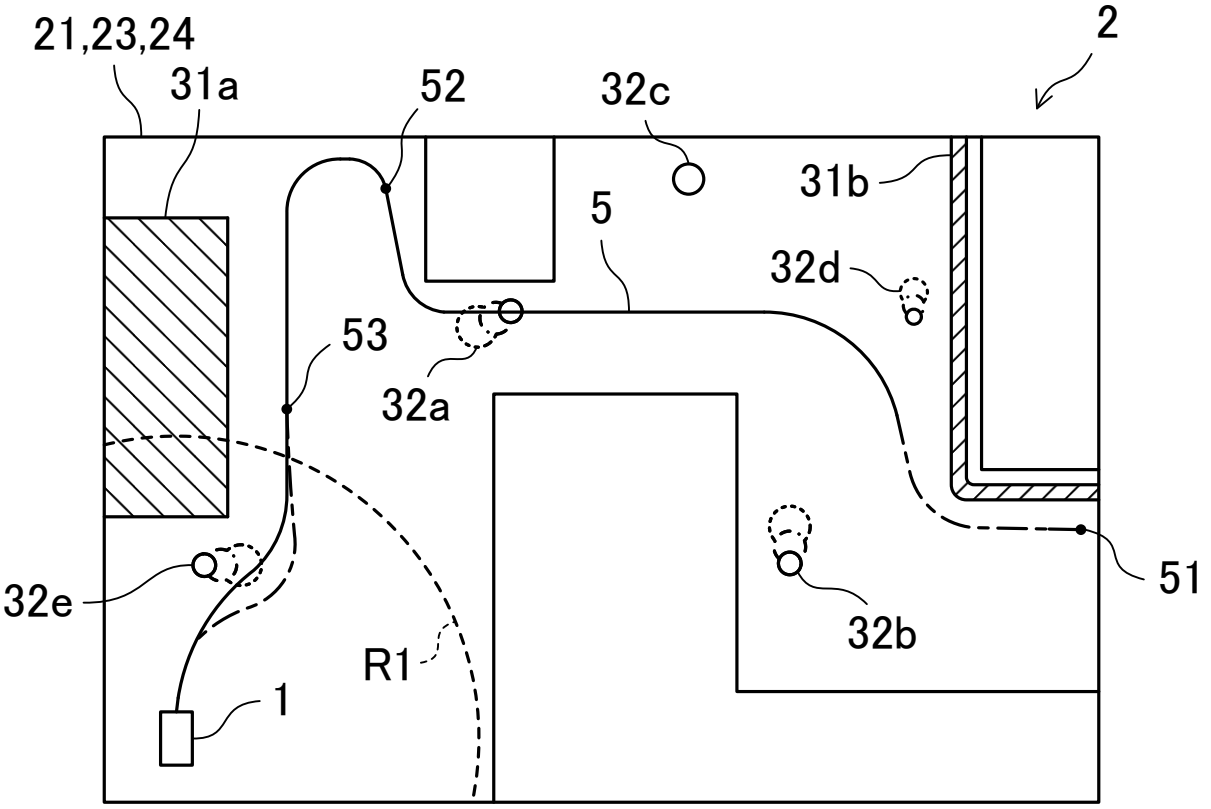

21,23,24
31a
52
32c
2
31b
5
32d
53
32a
32e
R1
32b
51
1

FIG. 22

