To return to ball collection area when done firing:

* Decide that we’re done firing
  + Nothing in loading mechanism after x second delay
* Continue until side wall switch triggered
* Drive about 1/3 of the way across based on time
* Convert to differential, turn 180
* Acquire middle tape (by driving forward and at a slight angle)
* Follow tape to collection area

To collect

* Follow tape back until one front switch triggers
* Pivot in appropriate direction until second switch triggers
* Wait a bit while pushing against wall with brush running
* Reverse slightly, angle to one side, drive forward into wall again
* Do same for other side. Repeat cycle as necessary

To return to wall

* Reverse straight from wall
* Do 180
* Acquire tape (any tape will work)
* When T detected, drive forward until front touch sensor trigger
* Turn on lasers, reverse until threshold is reached
* Convert to bicycle, move sideways following wall

Wall following

* Strafe sideways at constant distance from wall using PID algorithm, while detecting IR and side touch
* Detect IR:
  + Stop
  + (?) adjust so signal is strongest, adjust so parallel to wall
  + Spin-up firing at same time
  + Lift servo, confirm that lifter IR goes off
  + Fire
  + Wait with collection running for x seconds (possibly strafe in direction ball deflects)
* Detect side wall:
  + Reverse wall following direction