



Orange F  99% 08:56

**pfod** **Ardumower**    
connected


**Bump pressed on dock**  
**YES**

**Reverse Distance (CM) 50**  
  
0 200

**Roll Angle (Deg) 45**  
  
0 180

**Accel Distance after Roll 30**  
  
0 200

**Station check Distance 2**  
  
0 20

**Docking Speed % of MaxSpeed 65**  
  
20 100

**Force State to Station**

**Station**

**EXIT**

Set to YES if the Bumper is pressed when mower hit the station

When leave the station with timer it's rev distance

After reverse it's the roll angle

After Roll it's the straight line before arc circle to avoid station

When the mower detect the station it try to gently go forward to this distance to be sure the contact is OK

During the tracking the right sonar is used to reduce the speed when something is on the wire, see Robot::checkSonarPeriTrack() if you want to use other sonar

Only for test timer