Actions:

Get open: Move robot so it can receive pass to a list of points. Points can be weighted

Striker: deep support role. Gets open for goal and ball controller.

Fielder: shallow/rear support role. Gets open for ball controller and a striker.

Get open with ball: same as Get open, but no darting to better locations and uses dribble instead of move to.

Handle ball: High level ball control code. Chooses who to pass to or if the robot should dribble

Goalie: Guards the goal.

Orbit ball: rotate around a ball

Pass\_to: Passes to a robot

Dribble: moves the ball while maintaining control of it.

Ball intercept: Moves to gain control of the ball.

Move to: PID controller. Called by higher level actions

Cover: moves between a robot and a point.

Cover robot: moves between two robots.

Cover ball (obsolete): moves between a ball and a point (old goalie code)