```
+-------------------------------------------+
|                Controls                   |
+-------------------------------------------+
| L - Place          | r - range            |
| R - Delete         | p - processing       |
+--------------------+ m - mode             |
| c  - Clear         | s - Save             |
| q  - Quit          | l - Load             |
| i  - Toggle Instuct.| b - background      |
| e  - Toggle Energy | n - negate screen    |
| f  - Finite Run    | g - grab screen (JPG)|
| ^r - Neighbours Render | z - Toggle Convex|
| v  - Sensor Render | x - perimeter        |
+-------------------------------------------+
|                Dynamics                   |
+-------------------------------------------+
| 1 - Neigh Dist.  + ^1 | 4 - Obstacle Repel + ^4 |
| 2 - Min Dist.    + ^2 | 5 - Sample Rate    + ^5 |
| 3 - Bot Speed    + ^3 | 6 - Frame Rate     + ^6 |
+-------------------------------------------+
|                Physics                    |
+-------------------------------------------+
| 7 - Cohesion     + ^7 | 9 - Obstacle     + ^9 |
| 8 - Repulsion    + ^8 | 0 - Destination  + ^0 |
| a - Sensor Range + ^a | _ - Concave Press + ^_ |
+-------------------------------------------+
```

Frame - [10]/s[6]n [100]ms
Sample Rate   - [10]/s
Participant Speed - [20]
Minimum Distance   - [45]
Sensor Range   - [45]
Neighbour Range   - [60]
Obstacle Repulsion - [50]
Cohesion Physics   - [5]
Repulsion Physics - [15]
Obstacle Physics   - [100]
Destination Physics - [0]
Concave Physics   - [100]
BOT MODE.
NOT RECORDING.
INIFINITE RUN.
NOT PROCESSING.
NEIGHBOUR RENDERING.
ALL AGENTS
CONVEX COMPRESS.

PySwarm
By N. Eliot
0.2.7