Alice and Deividas, I need you two to complete the following tasks please

1. Improve the line following - using the LEGO sensors. Try to ensure that the robot jitters less, at this stage the custom sensors seems like it may not work fully so we are continuing with lego until further notice.
2. If the robot is **in the middle part** and an obstacle is detected, I need the server to be updated in the following format.

Position 20

T - Obstacle detected

F- Obstacle not detected

So if an obstacle is detected set position 20 as “T”, once the obstacle has been removed set position 20 as “F” // Done

This is to notify the user an obstacle has been detected

3. Once RoboTour has received commands for both user (in two user mode) or from the first user in single user mode, position 21 should be turned to “T”.

4. If the user presses skip, the robot should recalculate the whole path - as it does at the start - and update the server accordingly so the carousel can be updated // Done

5. If the user presses toilet or exit, the robot once getting their, should recalculate the whole route (as it does at the start). // Done

6. Thoroughly test the obstacle avoidance - we don’t want any surprises like in CD3 in the final demo.

Any questions please feel free to ask

Mahbub