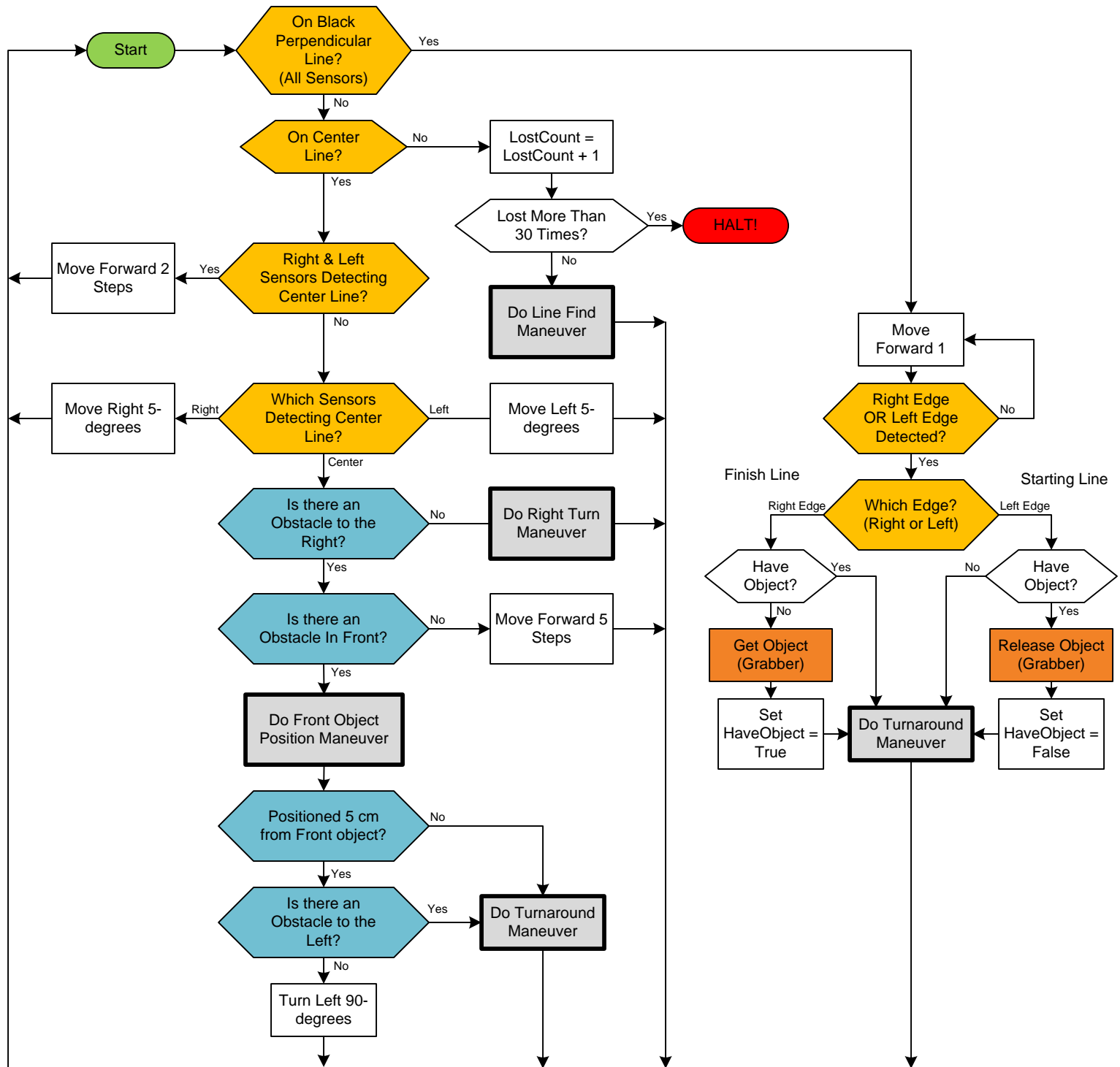


SJD_Maze_Find Program Flow

This diagram shows the program flow of the SJ Davis Robotics Maze Find program. This program demonstrates both line following and maze navigation using the ArcBotics Sparki robot platform. It uses the Infrared Reflectance Sensors to ensure that Sparki stays on the Maze centerline and is able to detect the START and END of the maze. It uses the Ultrasonic Range Finder to detect the maze walls and make navigation decisions. The various maneuvers are described in a separate document.



= Uses Infrared Reflectance Sensors to Make Decision



= Uses Ultrasonic Range Finder to Make Decision