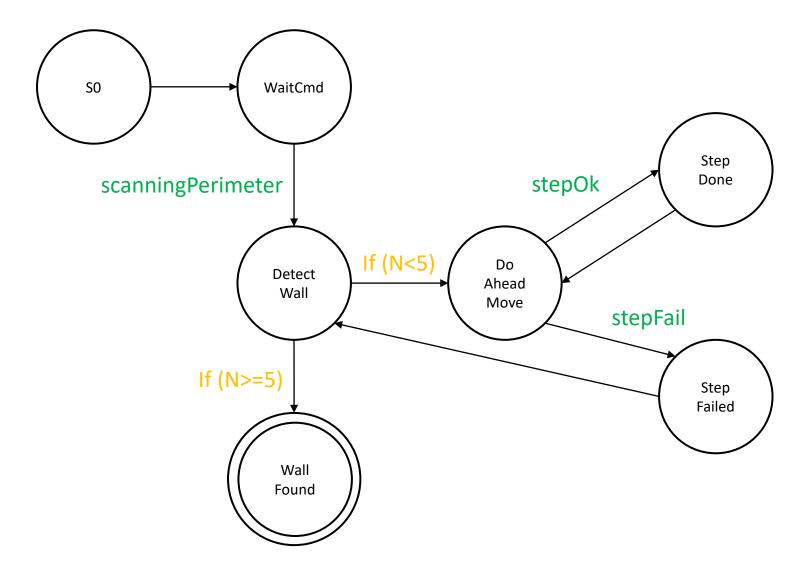
SPRINT 9

Room Perimeter Explorer



Timeout

Eventi

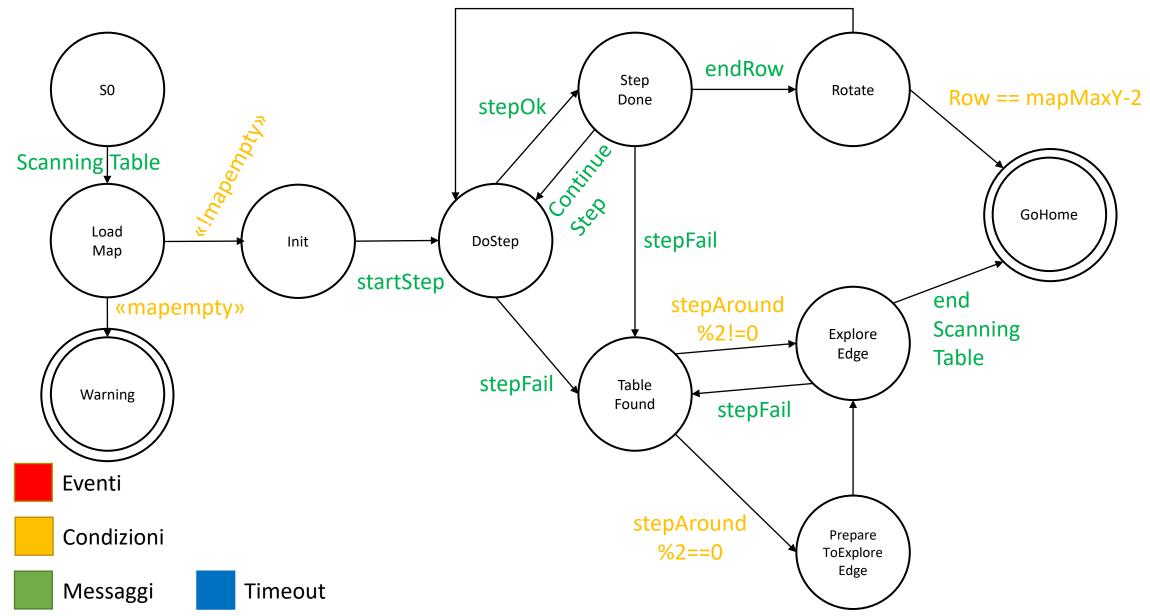
Condizioni

Messaggi

N = NumWallsFound

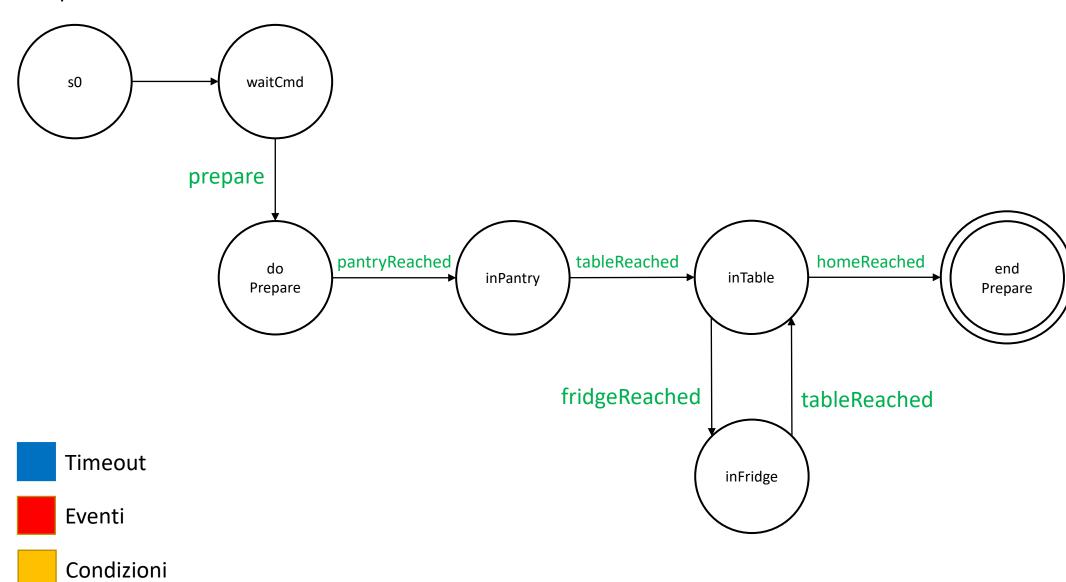
Find Table

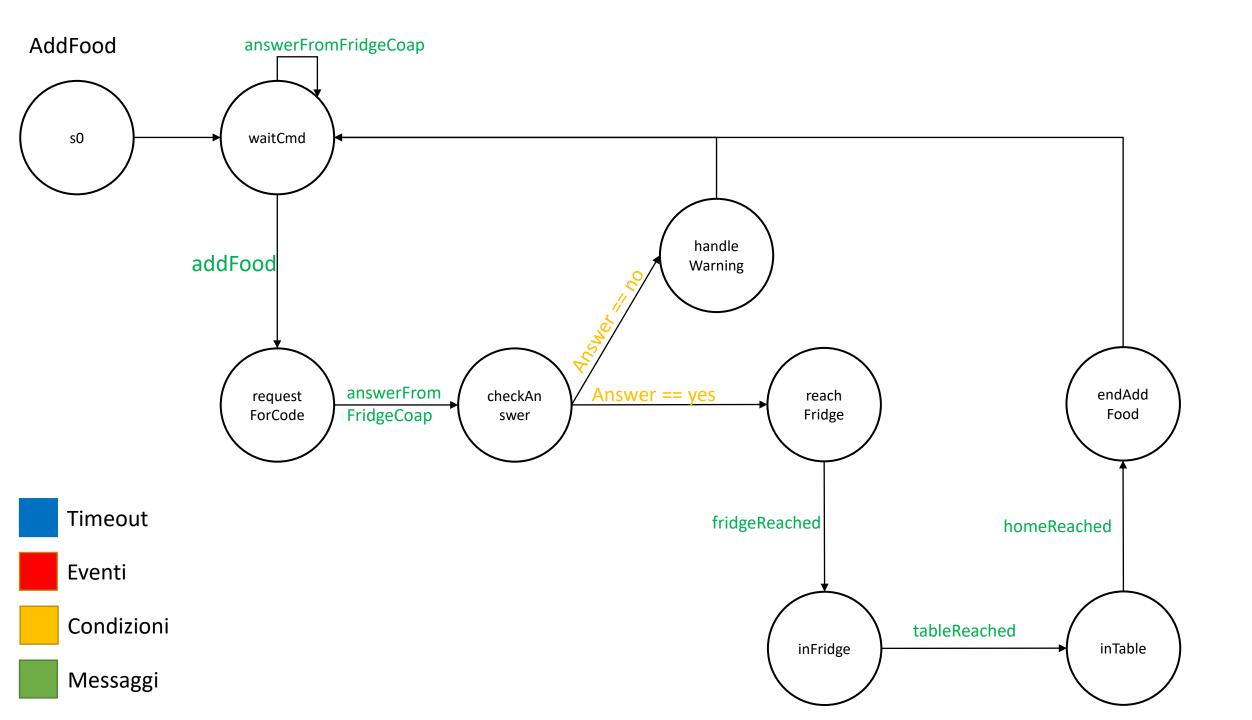
Row != mapMaxY-2



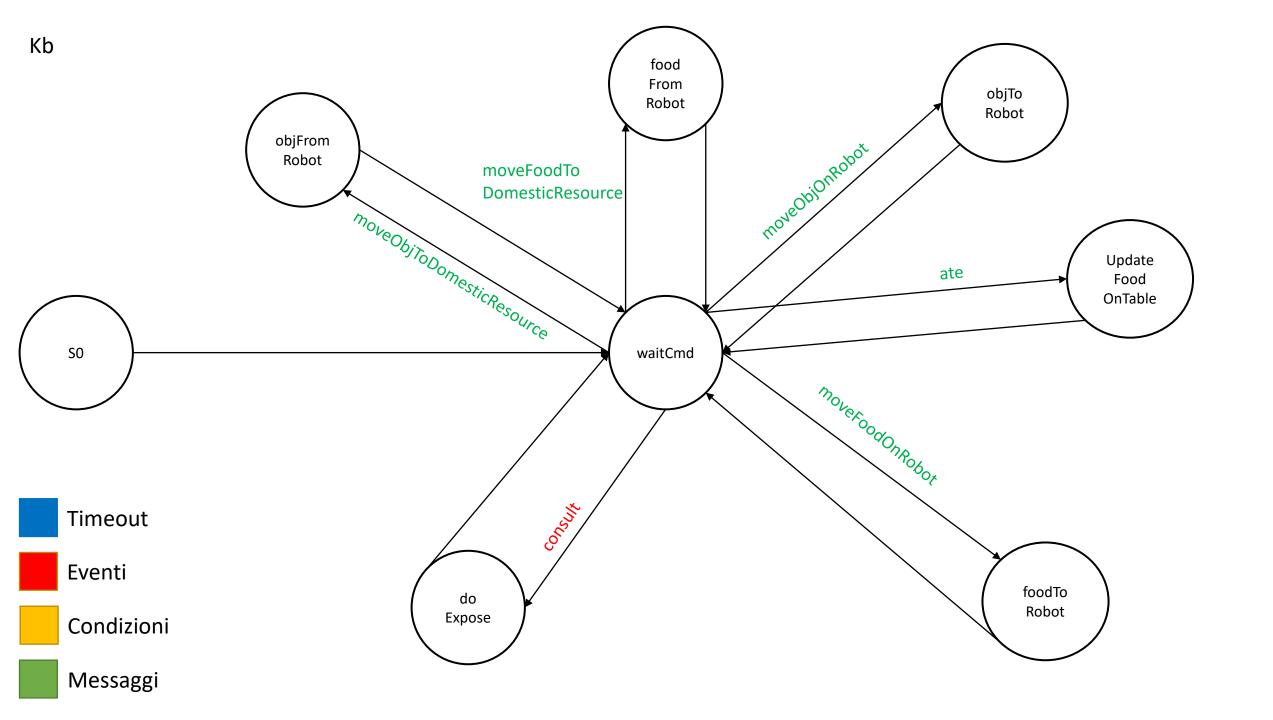
Navi update Robot Pos savePos wait Cmd handle EventR eactivat static Setup warning Room s0 reactivate stepOk plan handle make goalOk PathTo EventSt ThePlan Table stepFail stop reach startGoal return Request execute check doForw Home stepOk handle edGoal Planned AndDo $\operatorname{\mathsf{ard}} \operatorname{\mathsf{Mov}}$ StepOk Timeout Actions Action !curmovelsForward plan PathTo Eventi Applian do handle Condizioni Rotatio StepFail Messaggi

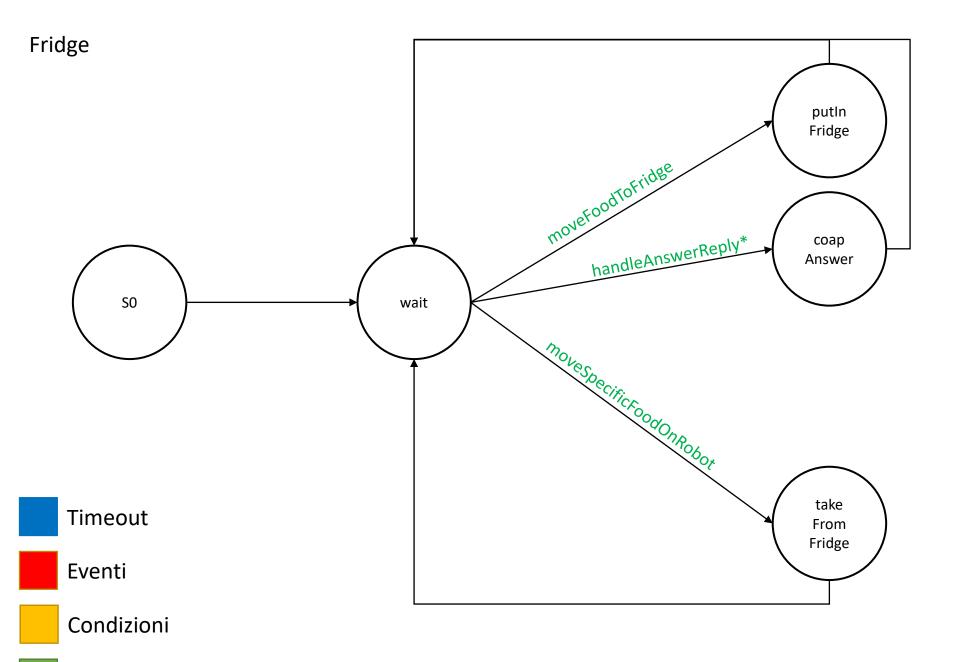
Prepare





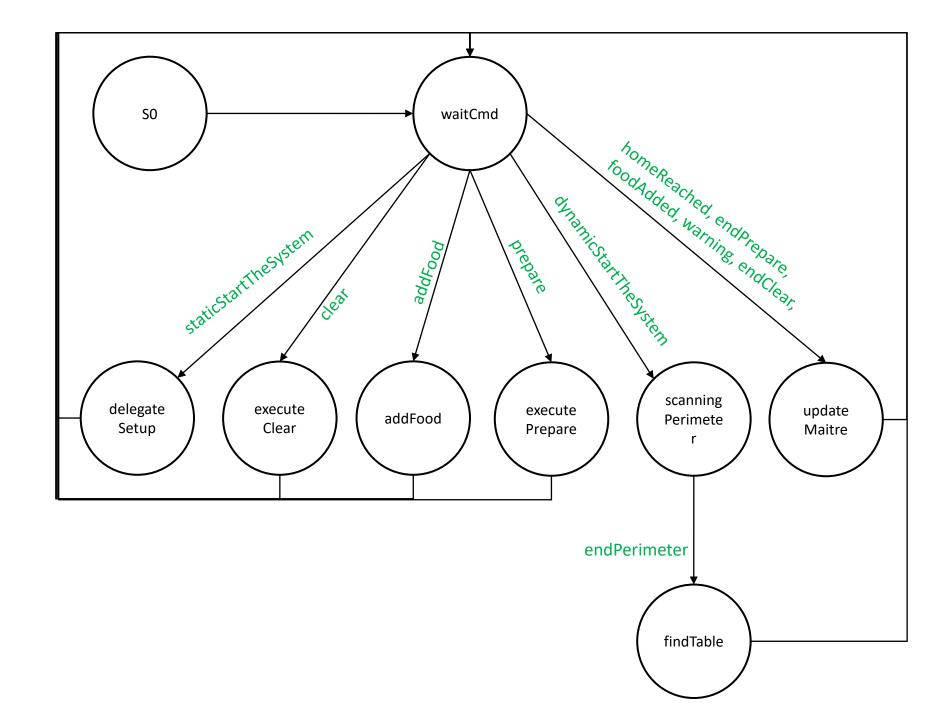
Clear s0 waitCmd clear fridgeReached tableReached homeReached reach inTable inFridge end ClearTable dishWasherReachedTimeout inDish Eventi Washer Condizioni





^{* =} da fridgeCoap.kt

RoomButler

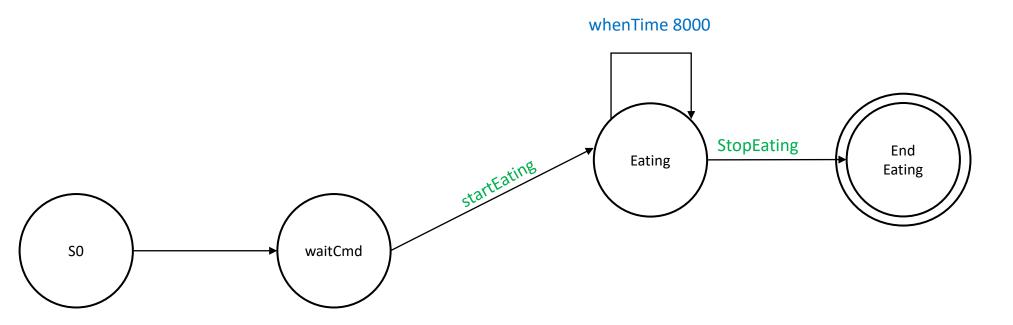


Timeout

Eventi

Condizioni

Greedy



- Timeout
- Eventi
- Condizioni
- Messaggi