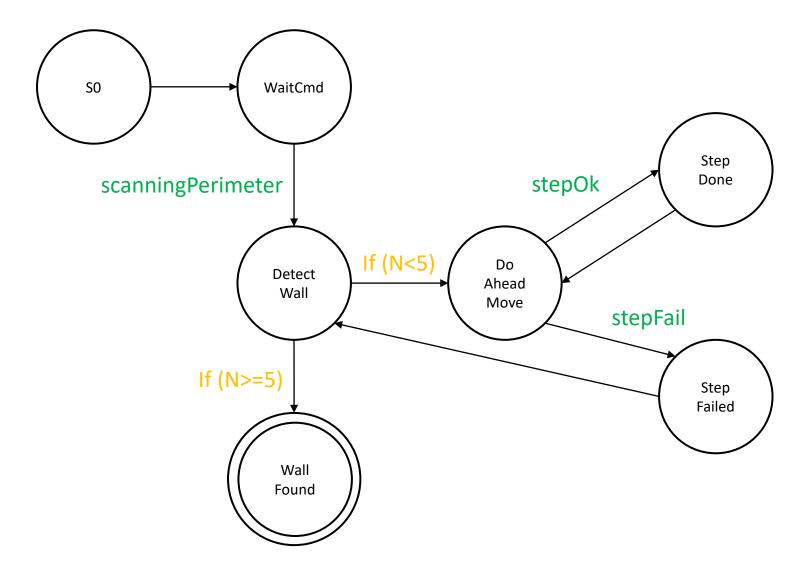
## SPRINT 10

## Room Perimeter Explorer



Timeout

Eventi

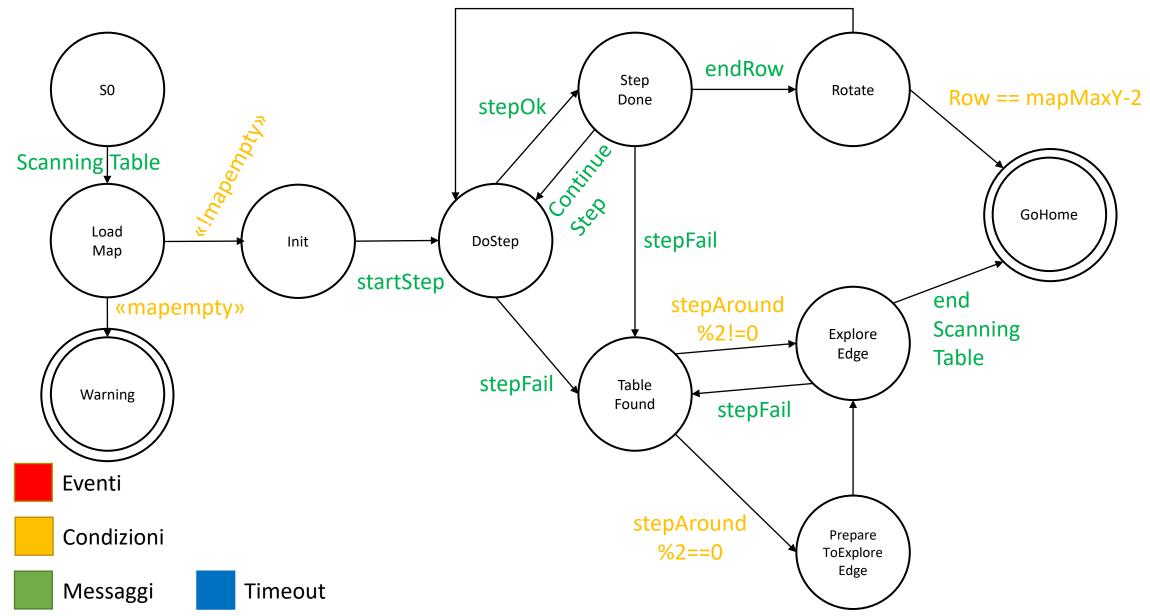
Condizioni

Messaggi

N = NumWallsFound

### Find Table

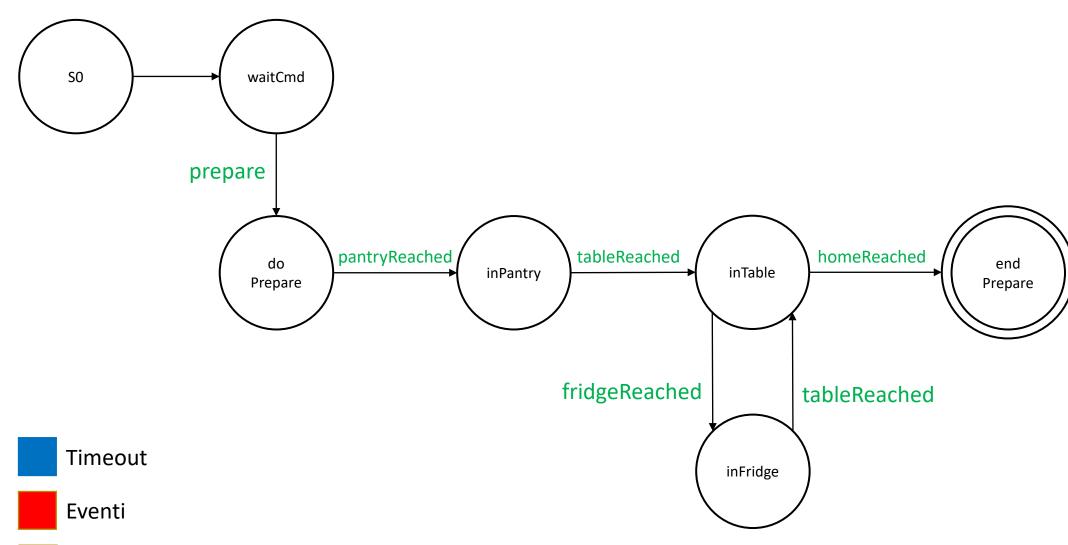
# Row != mapMaxY-2



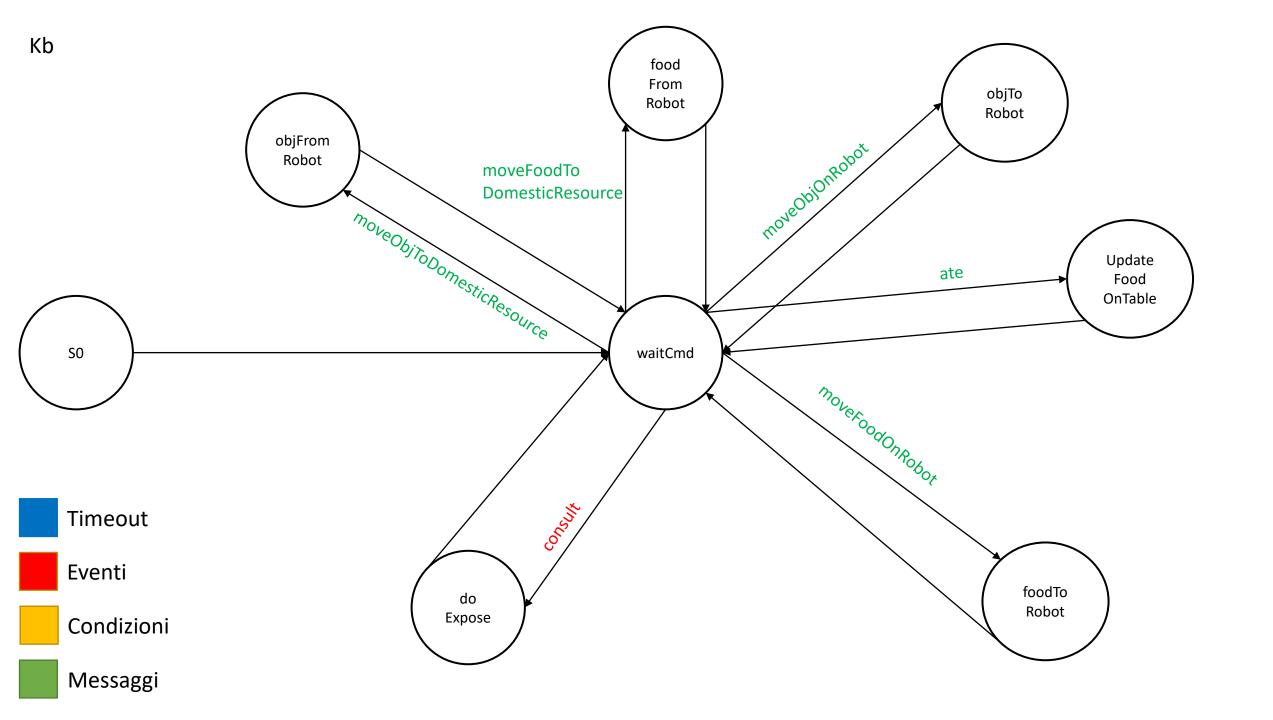
#### Navi update Robot Pos savePos wait Cmd handleE ventRe activate static Setup warning Room S0 reactivate stepOk plan handleE make goalOk PathTo ventSto ThePlan Table stepFail reach startGoal return Request execute check doForw Home stepOk handleS edGoal Planned AndDo $\operatorname{\mathsf{ard}} \operatorname{\mathsf{Mov}}$ tepOk Timeout Actions Action !curmovelsForward plan Eventi . PathTo Applian do handleS Condizioni Rotatio tepFail Messaggi

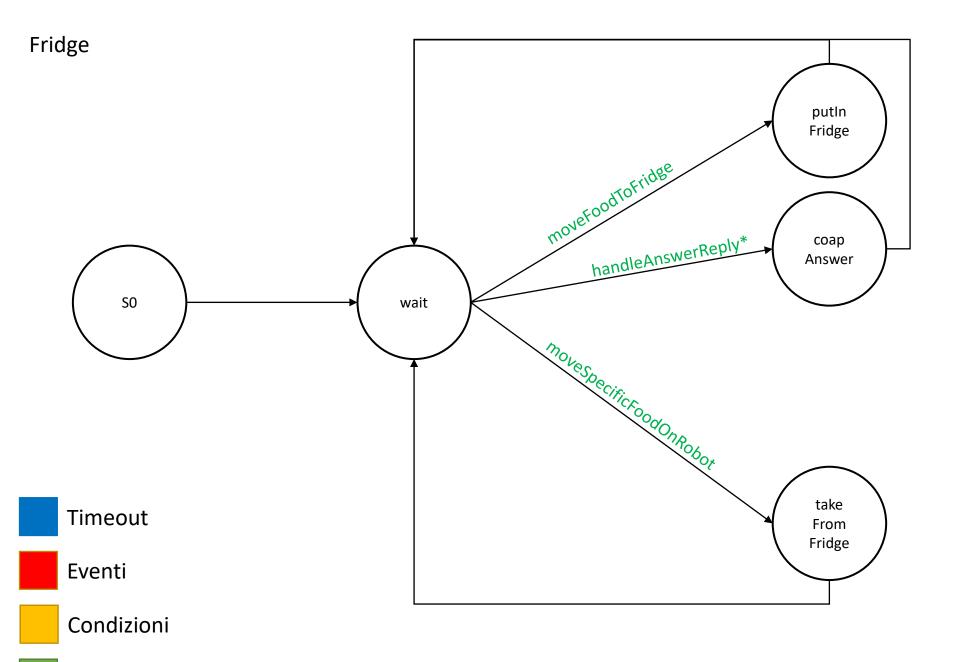
## Prepare

Condizioni

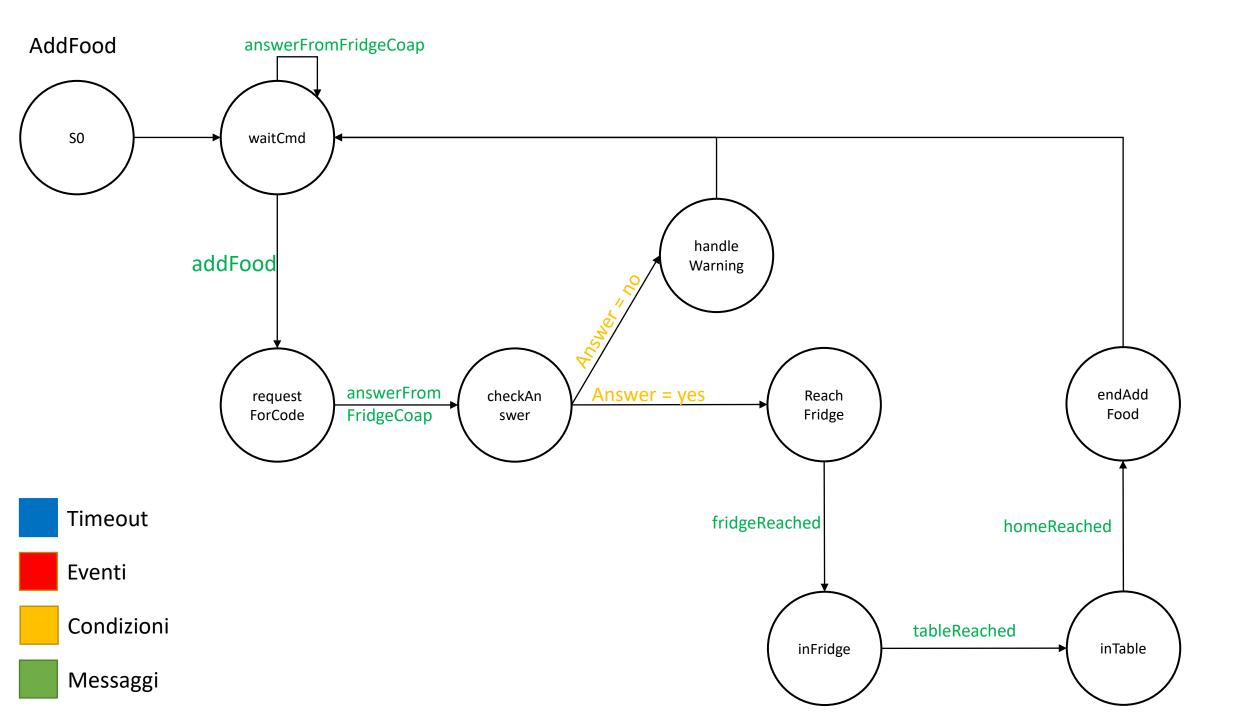


## Clear S0 waitCmd clear tableReached fridgeReached homeReached reach inTable inFridge end ClearTable dishWasherReachedTimeout inDish Eventi Washer Condizioni

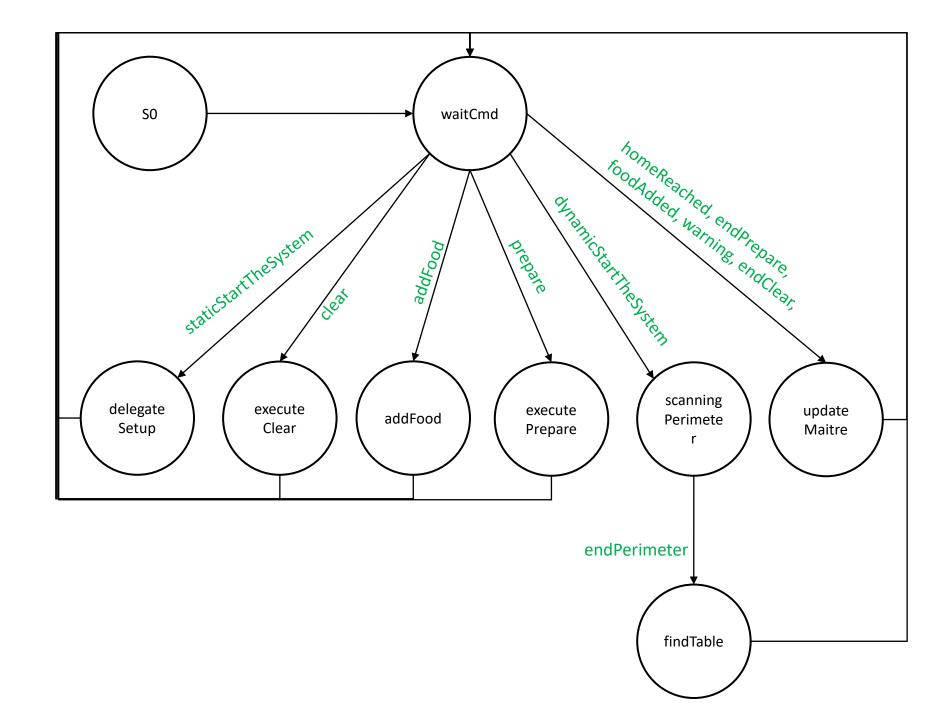




<sup>\* =</sup> da fridgeCoap.kt



## RoomButler

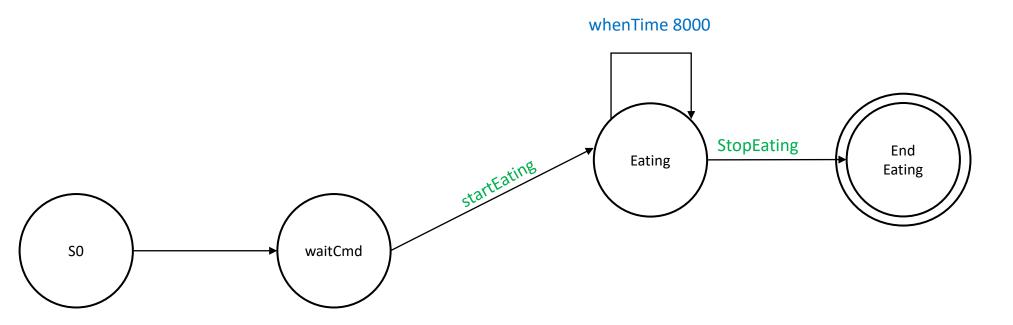


Timeout

Eventi

Condizioni

## Greedy



- Timeout
- Eventi
- Condizioni
- Messaggi