

0 stop()

R LinearVariables
R AngularVariables
i StopConstants

Inputs

i Sensors

Outputs

R Actuators

i

SetSpeed

entry output_left_motor(0); output_right_motor(0)

exec

[abs(lSpeed) <= LIN_SPD_ZERO / abs(aSpeed) <= ANG_SPD_ZERO]
/dist = 0; theta = 0; lSpeed = 0; aSpeed = 0

F

StopConstants

π LIN_SPD_ZERO: real = 0.001
 π ANG_SPD_ZERO: real = 0.001

ultrasonic: real

battery: nat