North

RoboticArm
Position: North

Workplace: 2

Workplace: 0

Workplace: 0

West

Workplace: 1

East

RoboticArm
Position: West

Workplace: 1

Workplace: 1

RoboticArm
Position: East

Workplace: 2

Workplace: 2

Workplace: 1

Workplace: 0

Workplace: 0

Workplace: 2

RoboticArm
Position: South

South

Orientation:

Orientation Example:

According to the orientation of RoboticArm in position North:

East is in position **Left**

South is in position **Mid**

West is in position **Right**

That position scheme is relative to the position of the RoboticArm. So it can be used with the same control signals from every positon

Positional Values:

Own:

Workplace 0:   LR: 100, UD: 25, BF: 40
Workplace 1:   LR: 50,   UD: 25, BF: 40
Workplace 2:   LR: 0,   UD: 25, BF: 40

Others:
Left Workplace 2:   LR: 100, UD: 15, BF: 72
Left Workplace 1:   LR: 59,   UD: 13, BF: 71
Mid Workplace 1:   LR: 50,   UD: 0,   BF: 100
Right Workplace 1: LR: 41,   UD: 13, BF: 71
Right Workplace 0: LR: 0,   UD: 15, BF: 72

LR: Left/Right, UD: Up/Down, BF: Back/Forth

Mechanics:

If a correct position is reached the interaction with that workplace is activated.

If the gripper is carrying a resource then it is possible to put that resource down on the reached workplace. But only if the workplace is not already used. OC: 100 -> to put resource down.

If the gripper is not carrying a resource then it is possible to pick up a resource.
OC: 0 -> to pick up resource.

OC=Open/Close: 1 <-> 99 no operation!