Mathis Bouverot-Dupuis

CNAM – ??

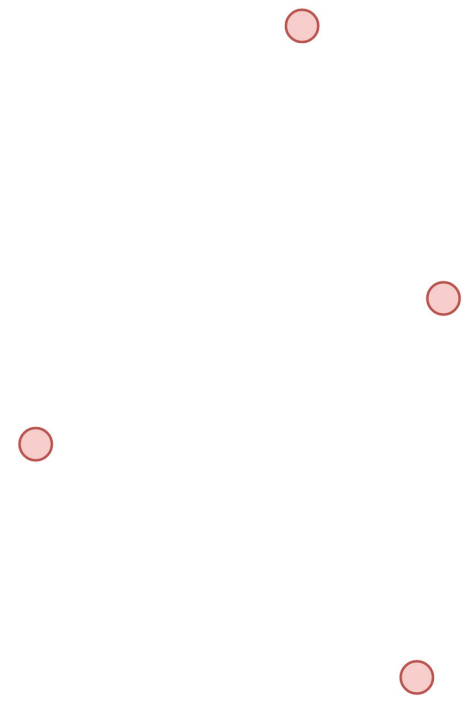
12 juillet 2022

Model

Suzuji & Yamashita's Model

Very simple (dumb) robots :

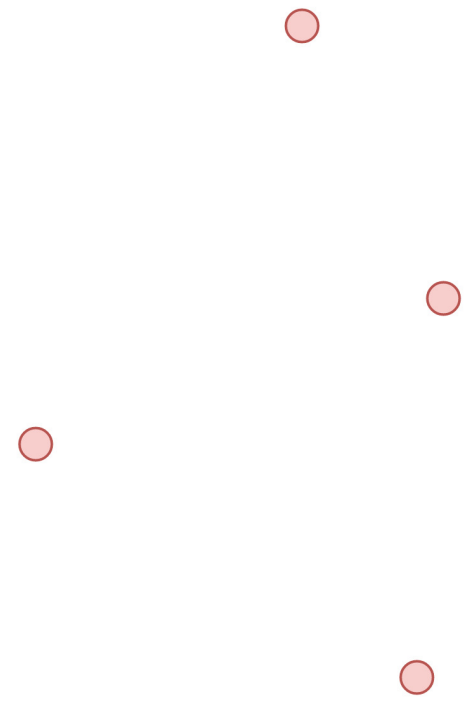
- Points in R^2 (can overlap)



Suzuji & Yamashita's Model

Very simple (dumb) robots :

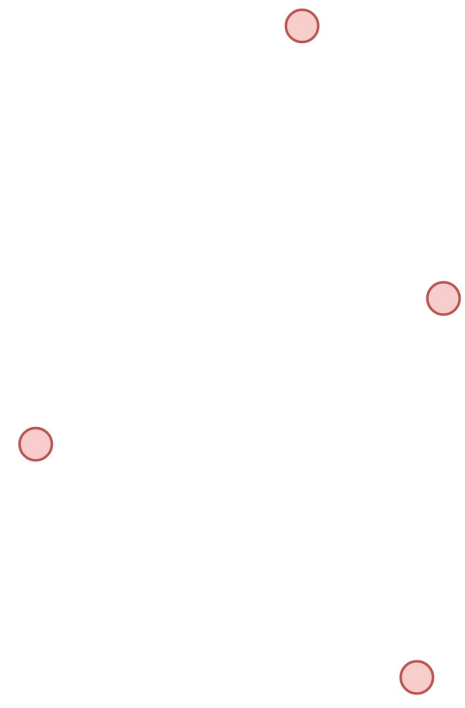
- Points in R^2 (can overlap)
- Anonymous



Suzuji & Yamashita's Model

Very simple (dumb) robots :

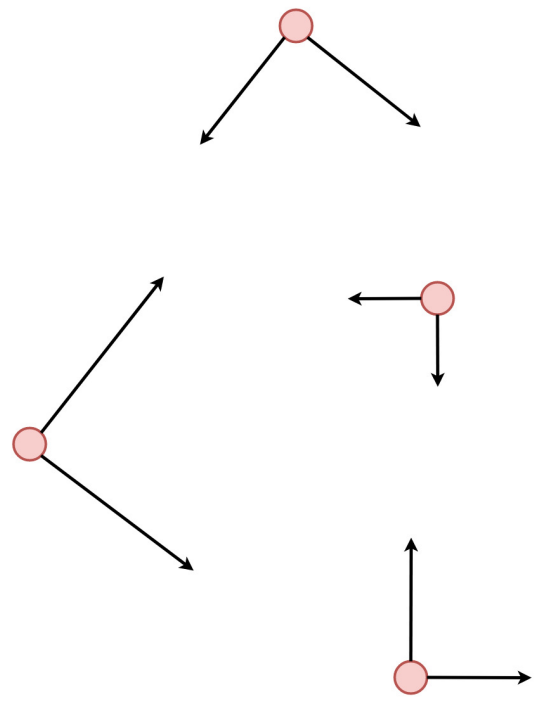
- Points in R^2 (can overlap)
- Anonymous
- No direct communication



Suzuji & Yamashita's Model

Very simple (dumb) robots :

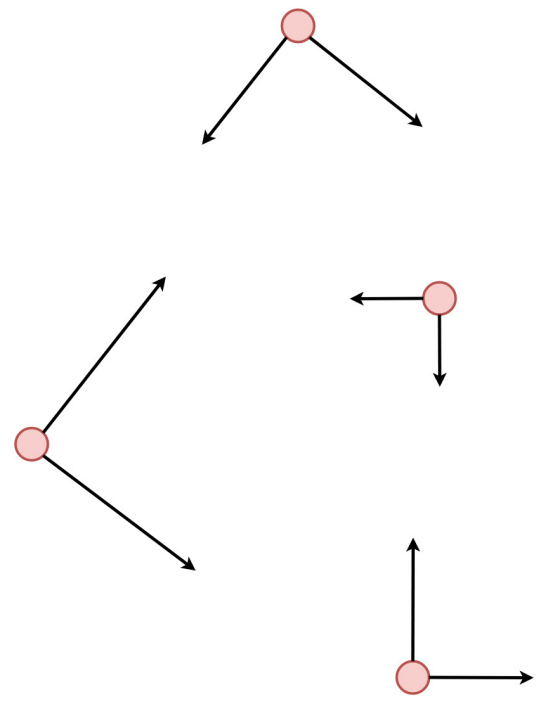
- Points in R^2 (can overlap)
- Anonymous
- No direct communication
- No common direction/scale



Suzuji & Yamashita's Model

Very simple (dumb) robots :

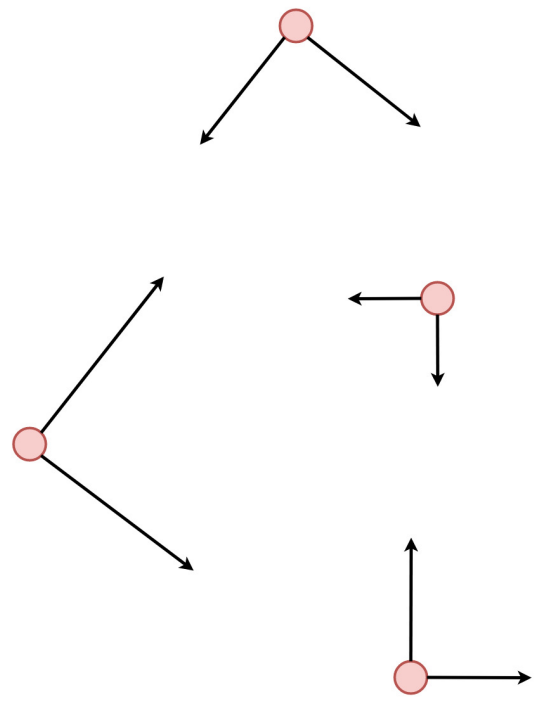
- Points in R^2 (can overlap)
- Anonymous
- No direct communication
- No common direction/scale
- Strong multiplicity detection



Suzuji & Yamashita's Model

Very simple (dumb) robots :

- Points in R^2 (can overlap)
- Anonymous
- No direct communication
- No common direction/scale
- Strong multiplicity detection
- Same robogram



Aligment : Goal

Goal : move robots to a common line, and make them stay on the line.

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Definition round (r:robogram) (da:demonic_action) cfg
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