//ROBOT 18

avatar\_ctrl Avatar doJob BaseRobotRight

%+% Executor<T extends ICommand> baseRobot(bottom) execute robotCommand(baseRobotRight,robotSpeed(robot\_speed\_medium),robotAngle(0)) by:it.unibo.iot.device.differentialdrive.impl.DifferentialDriveBaseRobot

%+% DifferentialDriveBaseRobot execute robotCommand(baseRobotRight,robotSpeed(robot\_speed\_medium),robotAngle(0))

%+% Executor<T extends ICommand> actuators(bottom) execute wheelCommand(wheel(wheelSpeed(fmedium)),wheel(wheelSpeed(rmedium))) by:it.unibo.iot.device.ddmotorbased.impl.MotorBasedDDActuators

%+% MotorBasedDDActuators leftWheel wheelSpeed(fmedium)

%+% MotorBasedDDActuators rightWheel wheelSpeed(rmedium)

%+% Executor<T extends ICommand> motor(left) execute motor(cw,motorSpeed(70)) by:it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% MotorDevice it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% Executor<T extends ICommand> motor(right) execute motor(ccw,motorSpeed(70)) by:it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% MotorDevice it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

//ROBOT initio

avatar\_ctrl Avatar doJob BaseRobotRight

%+% Executor<T extends ICommand> baseRobot(bottom) execute robotCommand(baseRobotRight,robotSpeed(robot\_speed\_medium),robotAngle(0)) by:it.unibo.iot.device.differentialdrive.impl.DifferentialDriveBaseRobot

%+% DifferentialDriveBaseRobot execute robotCommand(baseRobotRight,robotSpeed(robot\_speed\_medium),robotAngle(0))

\*\*\* QActorUtils ctxavatar created it.unibo.qactors.akka.SystemCreationActor@12b503c

%+% DifferentialDriveBaseRobot differentialDriveWheelsCommand=wheelCommand(wheel(wheelSpeed(fhigh)),wheel(wheelSpeed(rhigh)))

%+% Executor<T extends ICommand> actuators(bottom) execute wheelCommand(wheel(wheelSpeed(fhigh)),wheel(wheelSpeed(rhigh))) by:it.unibo.iot.device.ddmotorbased.impl.MotorBasedDDActuators

%+% MotorBasedDDActuators leftWheel wheelSpeed(fhigh)

%+% MotorBasedDDActuators rightWheel wheelSpeed(rhigh)

%+% Executor<T extends ICommand> motor(left) execute motor(cw,motorSpeed(100)) by:it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% MotorDevice it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% Executor<T extends ICommand> motor(right) execute motor(ccw,motorSpeed(100)) by:it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% MotorDevice it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

//ROBOT 18

avatar\_ctrl Avatar doJob BaseRobotLeft

%+% Executor<T extends ICommand> baseRobot(bottom) execute robotCommand(baseRobotLeft,robotSpeed(robot\_speed\_medium),robotAngle(0)) by:it.unibo.iot.device.differentialdrive.impl.DifferentialDriveBaseRobot

%+% DifferentialDriveBaseRobot execute robotCommand(baseRobotLeft,robotSpeed(robot\_speed\_medium),robotAngle(0))

%+% Executor<T extends ICommand> actuators(bottom) execute wheelCommand(wheel(wheelSpeed(rmedium)),wheel(wheelSpeed(fmedium))) by:it.unibo.iot.device.ddmotorbased.impl.MotorBasedDDActuators

%+% MotorBasedDDActuators leftWheel wheelSpeed(rmedium)

%+% MotorBasedDDActuators rightWheel wheelSpeed(fmedium)

%+% Executor<T extends ICommand> motor(left) execute motor(ccw,motorSpeed(70)) by:it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% MotorDevice it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% Executor<T extends ICommand> motor(right) execute motor(cw,motorSpeed(70)) by:it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% MotorDevice it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

//ROBOT initio

avatar\_ctrl Avatar doJob BaseRobotLeft

%+% Executor<T extends ICommand> baseRobot(bottom) execute robotCommand(baseRobotLeft,robotSpeed(robot\_speed\_medium),robotAngle(0)) by:it.unibo.iot.device.differentialdrive.impl.DifferentialDriveBaseRobot

%+% DifferentialDriveBaseRobot execute robotCommand(baseRobotLeft,robotSpeed(robot\_speed\_medium),robotAngle(0))

%+% DifferentialDriveBaseRobot differentialDriveWheelsCommand=wheelCommand(wheel(wheelSpeed(zero)),wheel(wheelSpeed(zero)))

%+% Executor<T extends ICommand> actuators(bottom) execute wheelCommand(wheel(wheelSpeed(zero)),wheel(wheelSpeed(zero))) by:it.unibo.iot.device.ddmotorbased.impl.MotorBasedDDActuators

%+% MotorBasedDDActuators leftWheel wheelSpeed(zero)

%+% MotorBasedDDActuators rightWheel wheelSpeed(zero)

%+% Executor<T extends ICommand> motor(left) execute motor(ccw,motorSpeed(0)) by:it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% MotorDevice it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% Executor<T extends ICommand> motor(right) execute motor(ccw,motorSpeed(0)) by:it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm

%+% MotorDevice it.unibo.iot.device.gpio.motor.impl.MotorGpioSoftPwm