DISCOVER

$broadcast(Reqf\,orSaf\,etyRegion(VR, \tau, id))$

CurrentSafetyRegion(m) → **WAITFORRESPONSE**

|MSG| = |R(VR)|

DECIDE

B

!A && !B && C

A && !B && id!=safestrobot

A && !B && id==safestrobot

msg → **INITIALIZE**

msg → **FORMING**

if (msg==D) → **JOIN**

AVOID

if (msg==D)

if (num(msg)==collision(R) && !D)

ACCEPT

COORDINATE

Rconf in e.ensemble_participants

FINISH

PLANNING

EXECUTION

LEGEND:

A= exists m in MSG where
m.ensemble_state="NO_ENSEMBLE"
B= exists m in MSG where
m.ensemble_state="INITIALIZE"
C=exists m in MSG where

m.ensemble_state="PLANNING&EXECUTION"
D=exists r in e where r.id>leader