1. Localization

* Record step vector.
* Avoid objects as you move.

1. Box Identification

* Colour.
* Signal “Found Box”
  + Send (x,y) coordinate to other robot.

1. Scan Box

* Find side furthest away from origin.
* Find steering positions.
* Store box corners as array/graph.

1. Signal e-puck

* Find furthest point on the other side.
* Tell other robot what side to steer.
* Other robot positioning.
  + Vector difference
  + Going round box

1. Pushing box to goal:

* To origin
* Finishes when both robots are at the origin
* Rotate
* Push