

Project 4

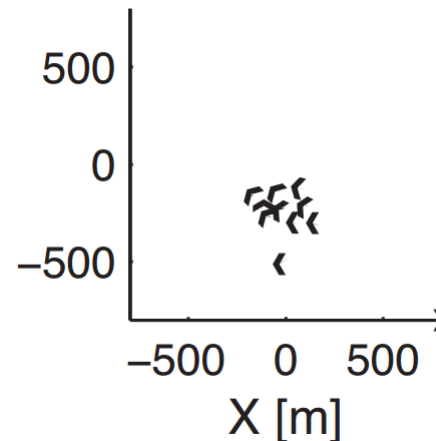
Based on paper 46: Reynolds flocking in reality with fixed-wing robots:
communication range vs. maximum turning rate

Due Nov 29, Noon

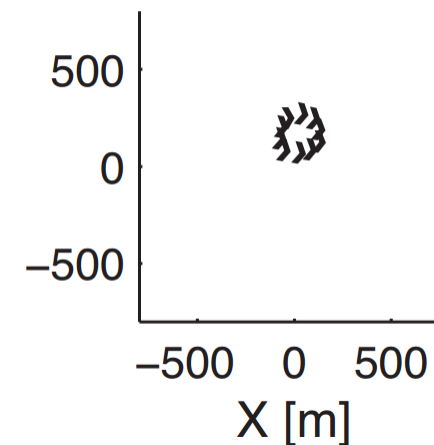
Goals:

1. Create a flock of 20 robots, which show good heading agreement
2. Will start in random positions and orientations
3. Ok to use id and position api
4. Will give infinite communication range,
 1. You can artificially reduce the communication range by filtering messages by distance
5. Use center of arena for location of migration force
6. Use new simulation code, which allows for a larger arena size

7. Create flocks that look like



not



Submission

- Submit:
 - usr_code.py
 - Image of best flock in action