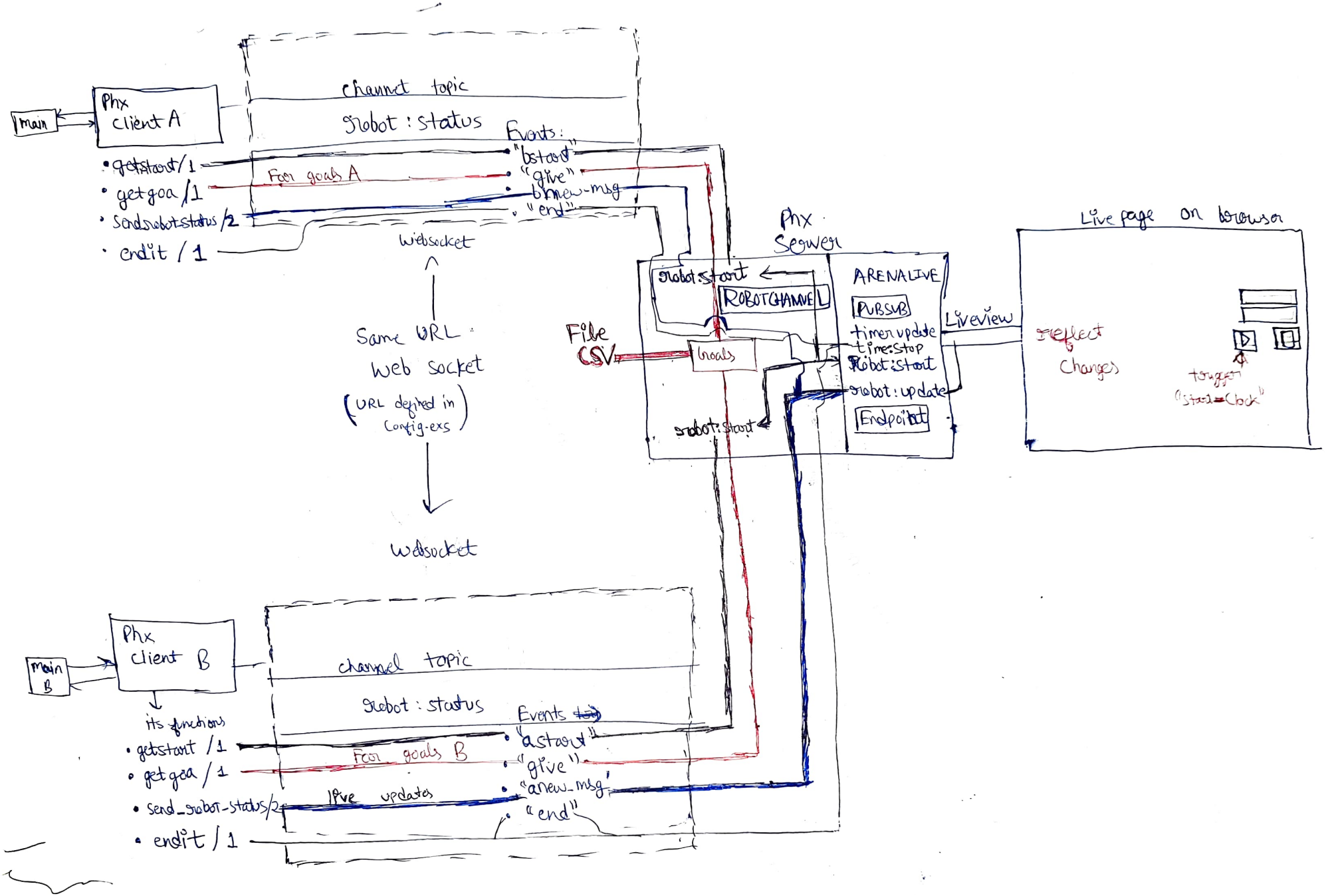
Phx client A
main
channel topic
robot : status
Events:
"bstart"
"give"
"anew-msg"
"end"
getstart/1
getgoa/1
sendrobotstatus/2
endit/1
For goals A
Websocket
Same URL
web socket
(URL defined in config.exs)
Websocket
Phx Server
robot:start
ROBOTCHANNEL
ARENALIVE
PUBSUB
timer:update
time:stop
robot:start
robot:update
Endpoint
File CSV
Goals
robot:start
Liveview
Live page on browser
Reflect changes
toggle "start-Clock"
Phx client B
main B
its functions
getstart/1
getgoa/1
send_robot_status/2
endit/1
channel topic
robot : status
Events
"bstart"
"give"
"anew_msg"
"end"
For goals B
give updates

main function of both clients:

1. get PID of channel robot status using,
   {:ok, channel} = PhoenixSocketClient.connect_server()
2. get start positions of Robot A/B using
   PhoenixSocketClient.getstart(channel)
3. start robot
   {:ok, robot} = start(x, y, facing)
4. get goal positions
   goals = PhoenixSocketClient.getgoa(channel)
5. execute "Stop/3" function which extracts x, y goal positions and calls
   StopA/B/5 which further calls "taskA" and "taskB" named functions to execute Path traversal and Obstacle avoidance is done through "leap" and "warp" functions.