

<<boundary>>  
i2cKommunikation

<<boundary>>  
colorSensor

<<controller>>  
mainPSoC

<<boundary>>  
Afstandssensor

<<boundary>>  
Scale

<<boundary>>  
motorStyring

initDistSens()

Init\_Color()

ADC\_init()

initMotor()

Initiere\_I2CKommunikation()

standardColor()

loop

[Så længe newOrder() returnerer 0]

newOrder()

handleOrderReceived(i)

alt

[Hvis newOrder() returnerer andet end 0]

BeertressWorkWork(type, table, amount)

driveForward()

Drive for one second to enter track

loop

[while distance >= 30]

getColor()

loop

[while color == 1] // farven rød

driveForward()

[while color == 2] // farven grøn

alt

[if tableCounter == table]

Tager øl

ADC\_Measure()

driveStop()

Vent på at vægt bliver < 0.246

driveForward()

driveStop()

ADC\_Measure()

Return to loop with newOrder()

[if tableCounter != table]

driveForward()

[while color == 3] // farven blå

driveRight()

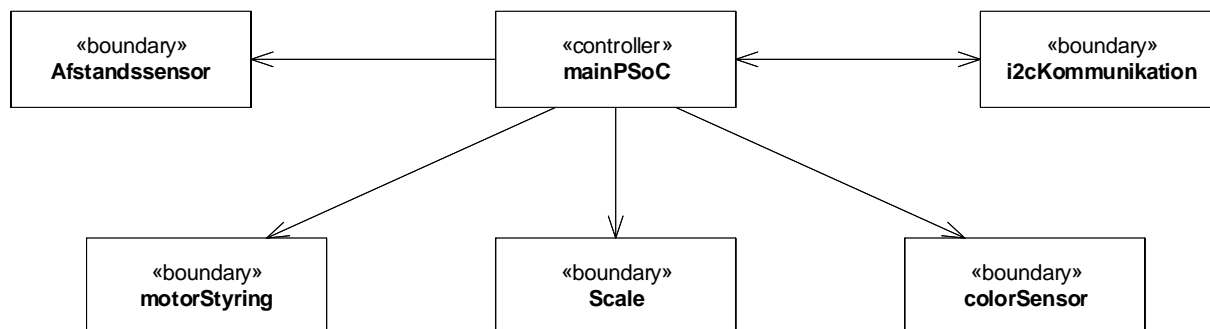
[while color == 4] // farven unknown

driveLeft()

[while distance < 30]

driveStop()

Class UC4



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