Setting the variables for the supervisor node

1. Make your robot, import it to the arena and name your robot node. (Give a DEF)
2. Open the file **"controllers/supervisor/supervisor.c"** from the shared project folder.
3. In **supervisor.c** change the ROBOT_NAME definition to the name of your robot.

```
10 //Change the defines accordingly
11 #define HIT_DELAY 1
12 #define STUCK_TIME 120
13 #define HIT_DIS 0.1
14 //Change the corresponding DEF robot name of the competitors
15 #define ROBOT_NAME "watson"
```

4. When you run the simulation, the supervisor node will do the following.
    a. Automatically put three boxes and your robot in the start positions. **The center of gravity of your robot should be well defined for correct operation.** (Your robot may go to the start position. But check the rotation of your robot before continuing the simulation. If the rotation of your robot is not in the way you want, pause the simulation, and rotate the robot as you need and continue the simulation)
    b. The supervisor node will inspect your robot and report the collisions with the wall.
    c. If the robot gets stuck for some time (default is set to 2 min) the supervisor node stops. If you want to continue the simulation with the supervisor node, restart the simulation after this happens.