```
┌─────────────────┐
│  WaitAtScanner  │
└─────────────────┘
         │  scan(code, scanStationID) [scanStationID == stationID] /
         │  dispatcher.reportLeaveStation(robotID, stationID),
         │  remote.send(robotID, Command::DriveToAndUnload,
         │              location.getUnloadPositionForCode(code))
         ▼
┌─────────────────┐
│     Deliver     │
└─────────────────┘
         │  receive(senderID, function) [senderID == robotID && function == Notification::Done] /
         │  stationID = dispatcher.requestNextStation(robotID, needsCharge)
         ▼
┌──────────────────────────────────────────────────────────────────────────┐
│  DriveBackToStation                                                        │
├──────────────────────────────────────────────────────────────────────────┤
│  entry / remote.send(robotID, Command::DriveTo, location.getArrivalPositionAtStation(stationID)) │
└──────────────────────────────────────────────────────────────────────────┘
         │  receive(senderID, function) [senderID == robotID && function == Notification::Done]
         ▼
        ◇ ─────────────[needsCharge == false]──────────────────────────────────────►
         │
         │ [else]
         ▼
                                        after(5s)
```