

# First experiments with robot simulator ARGoS: Programming composite behaviours

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## Exercise

Program a robot such that it is able to go towards the light avoiding collisions, i.e. the robot should be able to perform phototaxis with obstacle avoidance. To this aim, you may want to use the code developed in the previous exercises.

Compare the behaviour in the case without and with noise.

Try the controller also with more than one robot in the arena (just place a  $n$  robots randomly by using `distribute`). Is the control software still achieving the goal?

## Food for thought

- Analyse the performance of your control software and outline strengths and weaknesses.
- Think about the possible ways to combine two behaviours and the way they might interact.
- How would you assess the *performance* of the robot?