

# check grip position

Pre-condition: System is initialised

## (Controller)

1. check grip position

## (AccelerationControl)

2. retrieve grip position
3. call ROS publisher
4. a. robot is stationary  
b. robot is moving

[route a]

Pre-condition: matrix is **not** RED

5. light matrix BLUE

[route b]

6. a. arm is folded  
b. arm is **not** folded

## (LEDControl)

[route ba]

Pre-condition: matrix is **not** RED

7. light matrix BLUE

[route bb]

8. light matrix RED

## (Controller)

9. wait for next period

Post-condition: Matrix is lit in appropriate color