On rising edge of sig\_clock, check which robot sent signal. Set flag.

Check values based on flags and reset flags.

Update tables based on new data.

Update robots w/ new tables. If close to boundary or obstacle, send clock and signal to robot

Robot receives sig\_clock from processing, looks at values.

Transmits values to server.

Server takes values.

Data Structures

Processing table in processing

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
|  | Bound | Obstacle | Grid | x\_dist | y\_dist |
| Robot 1 |  |  |  |  |  |
| Robot 2 |  |  |  |  |  |

Server table in processing

|  |  |
| --- | --- |
|  | mov |
| Robot 1 |  |
| Robot 2 |  |

Obstacle table in processing

|  |  |  |  |
| --- | --- | --- | --- |
|  | Grid | x\_dist | y\_dist |
| Robot 1 |  |  |  |
| Robot 2 |  |  |  |

Status Table in server

|  |  |  |  |
| --- | --- | --- | --- |
|  | Grid | Next grid | Mov |
| Robot 1 |  |  |  |
| Robot 2 |  |  |  |