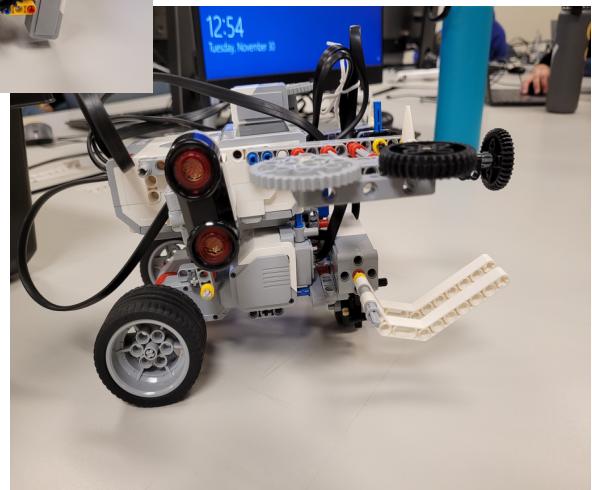
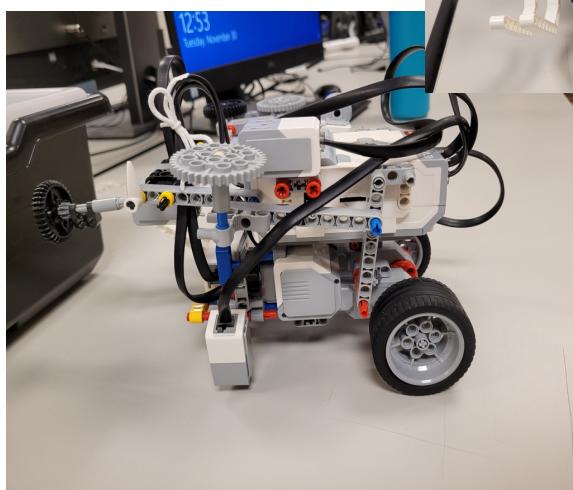
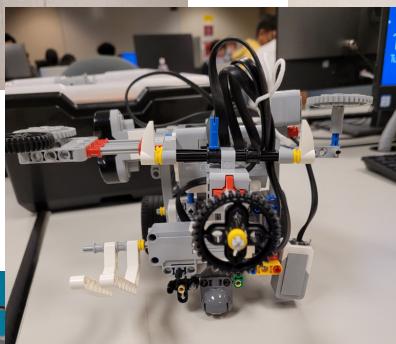
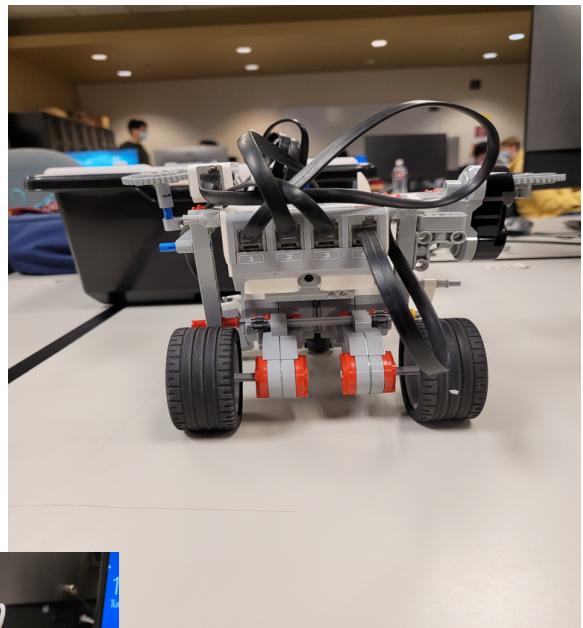
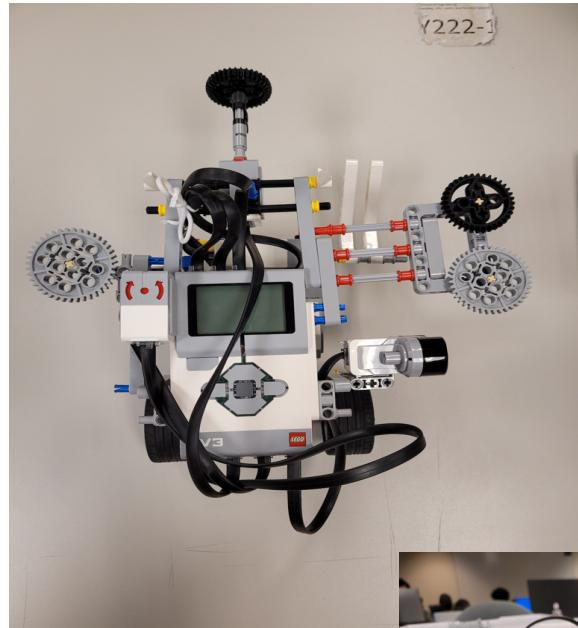


Team 11: Demonstration Report

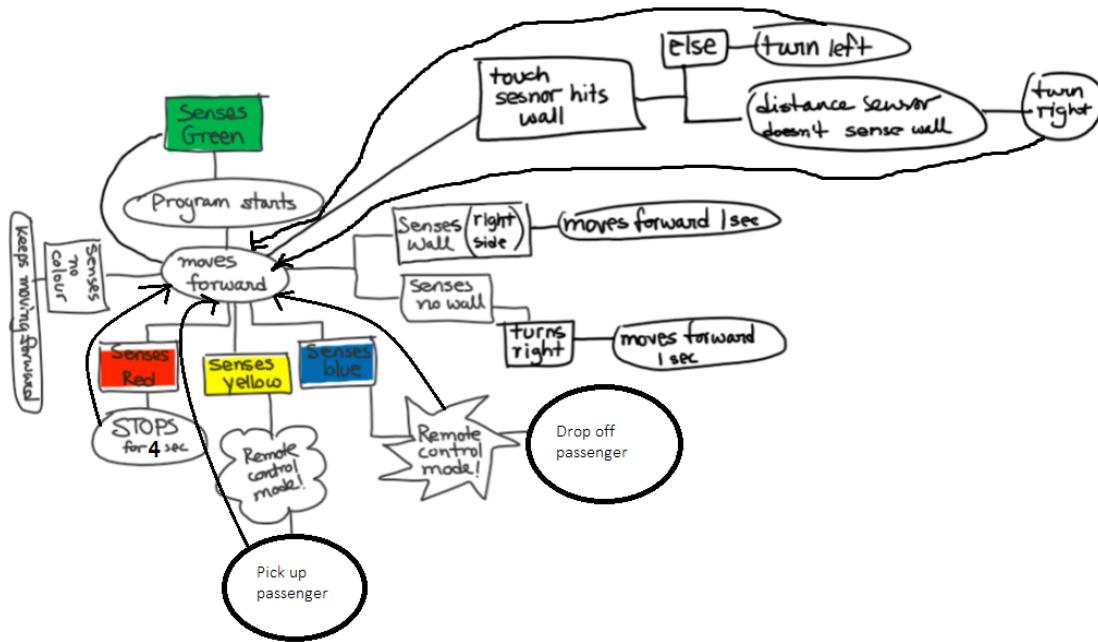
Abraham Lozano Serna, Jessie Frey, Madeleinne Tan, Anouska Barua

Final Design



Description of Behavior

This is our robot's state diagram, assuming that the state diagram starts at the "senses green" stage. When the car senses red, it is supposed to stop for 4 seconds. When the car senses yellow, it picks up the passenger in remote control mode. Whoever would control the car must quit from the remote control mode before letting the car back into the maze. When the car senses blue, it switches back to remote control mode and the user can drop off the passenger. When it goes back to green, it stops because that is supposed to be the end of the maze run. Additionally, the car has certain stages and actions if it detects walls, such as letting the nose touch the front wall before turning left. Or, if it doesn't sense a wall in a time window, it turns right.



Links to Video and Code

- [LINK TO VIDEO](#)
- [FINAL CODE AS A ZIP FILE](#)