delta\_back <-

delta\_left <-

delta\_right <-

parent\_id <- id - 1

child\_id <- id + 1

status <- None

msg <- receiveMsg()

if msg.dest\_id == id and msg.src\_id == parent\_id

then parent\_pos <- msg.src\_pos

status <- msg.status

target\_pos <- msg.target\_pos

parent\_id <- msg.new\_parent

if status == Leader

then if not destination\_reached

goTo(area\_lead\_position)

PublishMsg(id, child\_id, my\_pos, None, my\_pose + delta\_back, id)

else

PublishMsg(id, child\_id+1, my\_pos, Left, my\_pose + delta\_left, id)

PublishMsg(id, child\_id+2, my\_pos, Right, my\_pose + delta\_rightt, id)

if not area\_covered

PublishMsg(id, child\_id + 3, my\_pos, Center, my\_pose + delta\_back, id)

else

PublishMsg(id, child\_id + 3, my\_pos, None, my\_pose + delta\_back, id)

else if status == None

then goTo(target\_pos)

PublishMsg(id, child\_id, my\_pos, None, my\_pose + delta\_back, id)

else if status == Center

PublishMsg(id, child\_id+1, my\_pos, Left, my\_pose + delta\_left, id)

PublishMsg(id, child\_id+2, my\_pos, Right, my\_pose + delta\_rightt, id)

if not area\_covered

PublishMsg(id, child\_id + 3, my\_pos, Center, my\_pose + delta\_back, id)

else

PublishMsg(id, child\_id + 3, my\_pos, None, my\_pose + delta\_back, id)

else if status == Left or status == Right

if not reached target\_pos

goTo(target\_pos)

PublishMsg(id, child\_id, my\_pos, None, parent\_pos + delta\_back, parent\_id)

else

doLawnMowerScanning()