activate fre collision avoidance fishspositions & Control Mode behavior zobot's position Robot ID resolver calls to cheek · manual > (Se Vz) ecids - links the id's obstade avoidance (a schon) if the motion is sal Motion Safety [at signal] and rolds positions osition · trajectory -> target point - cheeks 1f o model -> target point it's safe to racker or simulator · Straight aheard - (20=2) Control loop follow the care target motors speed at signal] · idle -> (ve= 2/2=0) target OR Harpet position - act vate "collision" if use C++ / det / on Timer OR const calls step() Motion Cantrol GUI Speed Steps the Constrol Hode &M cet/get with fishes & TRATI - chiedes if the results Control 20 bot's position - Sets aurent . fish be hovioz Moell Cot signed are case isets the mode from was Control Mode OTTO. - asks MotionStockery to - get set in whose - shows accreat ONTOl Mode & "obstacle control mode 1- calls step () with the State Machine ausidance! control mode zerules of State machine ? 1 obstade avoidance Mo tron Commands Constrol Mode sestores - ceeps the ever eng low battery " - converts the current todal as imput done with OA. current compra tought positions to the events (block mode & executes [Q+ Signal] mosoz commands its step () - sends the motoz Ecttings (for a went) commands cet/est Zobote extitings get 1 get ASEBA bridge sends the motors [Cee/Q+/Singleton Lobot Condrol Seffinge 1 uneue pt? Commands [Q+, c++, singlefon] (1) now collision avoidant - receives/ suids [R+ signal] - exores parameters of bahawioz that generales events from fish 6+5 to RiBot control modes & major - diarges scripts a tragectory to avoid strategy -provides the list colisions Robot Transmitter regols Twittes * of connected fish bots - Sends commands config file to Ribots ELISON / RM CT control maps (define the area specific behavior) tile system I grayceale . bmp] + ozolez in which *shared Wigh tracking