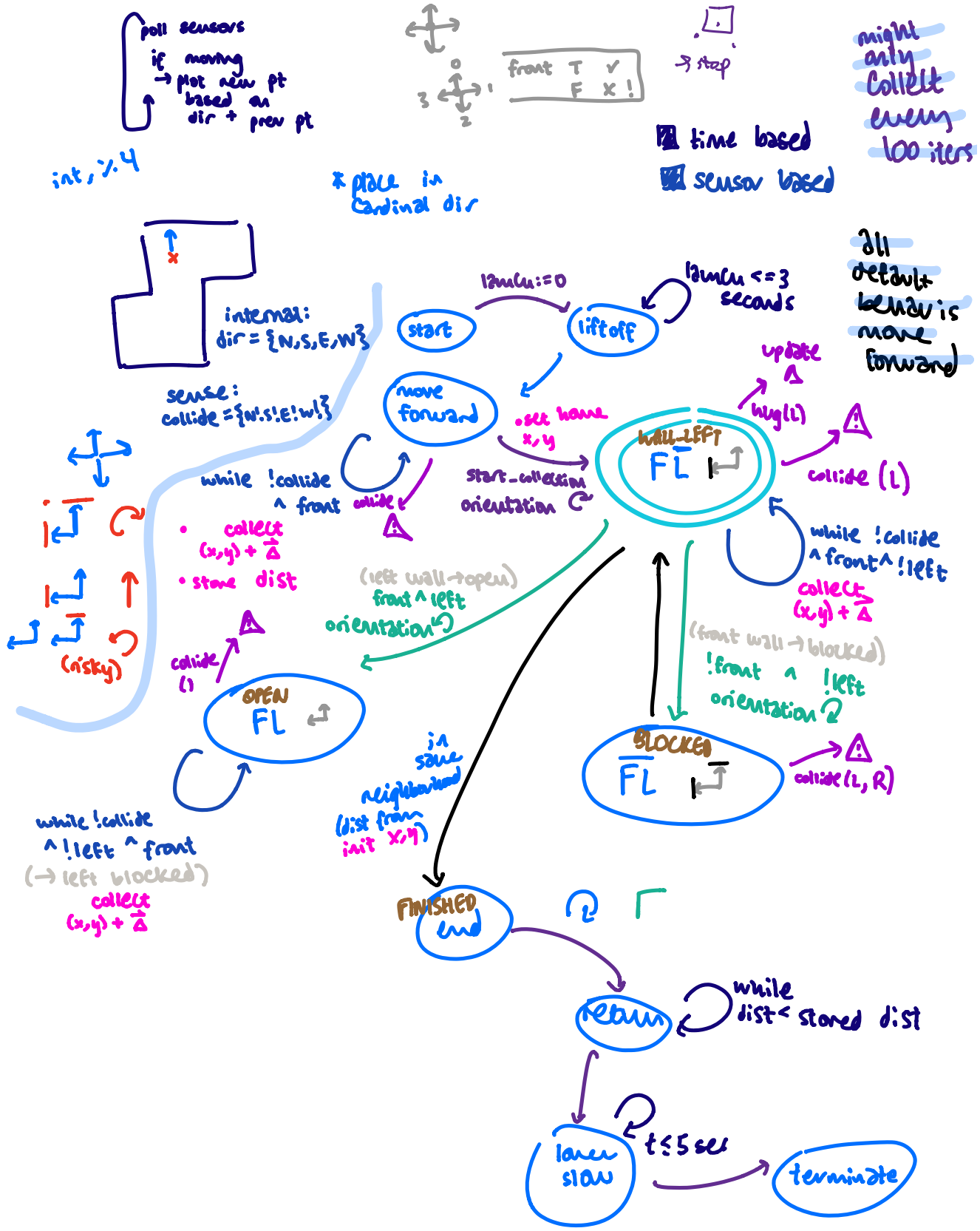
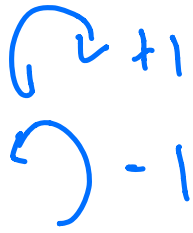

poll sensors
if moving
→ plot new pt based on dir + prev pt
int, x, y
front T ✓
F X !
step
might only collect every 100 iters
time based
sensor based
* place in cardinal dir
internal:
dir = {N,S,E,W}
sense:
collide = {w,s,e,w}
launch := 0
launch <= 3 seconds
start
liftoff
all default behav is move forward
move forward
set home x,y
update
wig(L)
WALL_LEFT
FL
collide (L)
start_collection orientation
while !collide ^ front
collide
collect (x,y) + Δ
store dist
while !collide ^ front ^ !left
collect (x,y) + Δ
(left wall → open)
front ^ left
orientation
(front wall → blocked)
!front ^ !left
orientation
(risky)
collide (L)
OPEN
FL
BLOCKED
FL
collide (L, R)
in same neighborhood (dist from init x,y)
while !collide ^ !left ^ front
(→ left blocked)
collect (x,y) + Δ
FINISHED
end
return
while dist < stored dist
lower slow
t ≤ 5 sec
terminate

for all transitions:
- stop collection
- stop draw
- rotate
- update $\vec{\Delta}$
- start mvmt



front := # - or = 0