RaspberryPi

- □ resumePulse : bool
- □ stop : bool
- □ stopPulse : bool

- ● RaspberryPi()
- ● ~RaspberryPi()
- ● consumeResumePulse() : bool
- ● consumeStopPulse() : bool
- ● getStop() : bool {query}
- ● readStopCommand() : void

E RotationDirection

LEFT
RIGHT

E State

ADVANCING
DETAINED
REVERSING
TURNING

ArduinoRobot

- □ motor_l1 : AF_DCMotor
- □ motor_l2 : AF_DCMotor
- □ motor_r1 : AF_DCMotor
- □ motor_r2 : AF_DCMotor
- □ servo_motor : servoMotor
- □ sonic_sensor : ultraSonic

- ● ArduinoRobot(ultraSonic us, servoMotor sm)
- ● ~ArduinoRobot()
- ● measure_distance() : float
- ● chooseTurnDirection() : int
- ■ clampSpeed(int s) : int
- ● advance(int speed_left, int speed_right) : void
- ● goLeft(int speed_left, int speed_right) : void
- ● goRight(int speed_left, int speed_right) : void
- ● init() : void
- ● reverse(int speed_left, int speed_right) : void
- ■ setLeft(int speed, uint8_t dir) : void
- ■ setRight(int speed, uint8_t dir) : void
- ● setServoAngle(int angle) : void
- ● stop() : void

servoMotor

- ○ servo : Servo
- ○ servoPin : int

ultraSonic

- ○ echoPin : int
- ○ trigPin : int