EXPLORATION – INTERACTION

For a test purpose, there are 2 kind of explore commands:

* **explore : explore**, this message is sent from Console to Robot to command the exploration;
* **explore : explore ( START , BOUNDS )**, this message includes more data and is used during the tests to set the start position of the Robot and the map boundaries.  
  START is position ( X , Y ), and is the start robot position;  
  BOUNDS is map ( WIDTH , HEIGHT ), and is the maximum map boundaries.  
    
  Whit this command is possible to show the map at runtime during the exploration on the GUI of the Console.

I prefer the message form because I don’t want to lose this information.

Then we need something to ménage the other features:

* **expdata : expdata ( POS , STATE)**, is a message from Robot to Console and is used to notify the new Cell state.  
  POS is position ( X , Y ) and STATE can be “clear” or “object”.
* **abort : abort**, is an event emitted by the Console in order to stop the exploration phase. This is the same of the navigation phase;
* **end : end**, is and event emitted by the Robot in order to notify the end of the exploration. This is the same of the navigation phase;