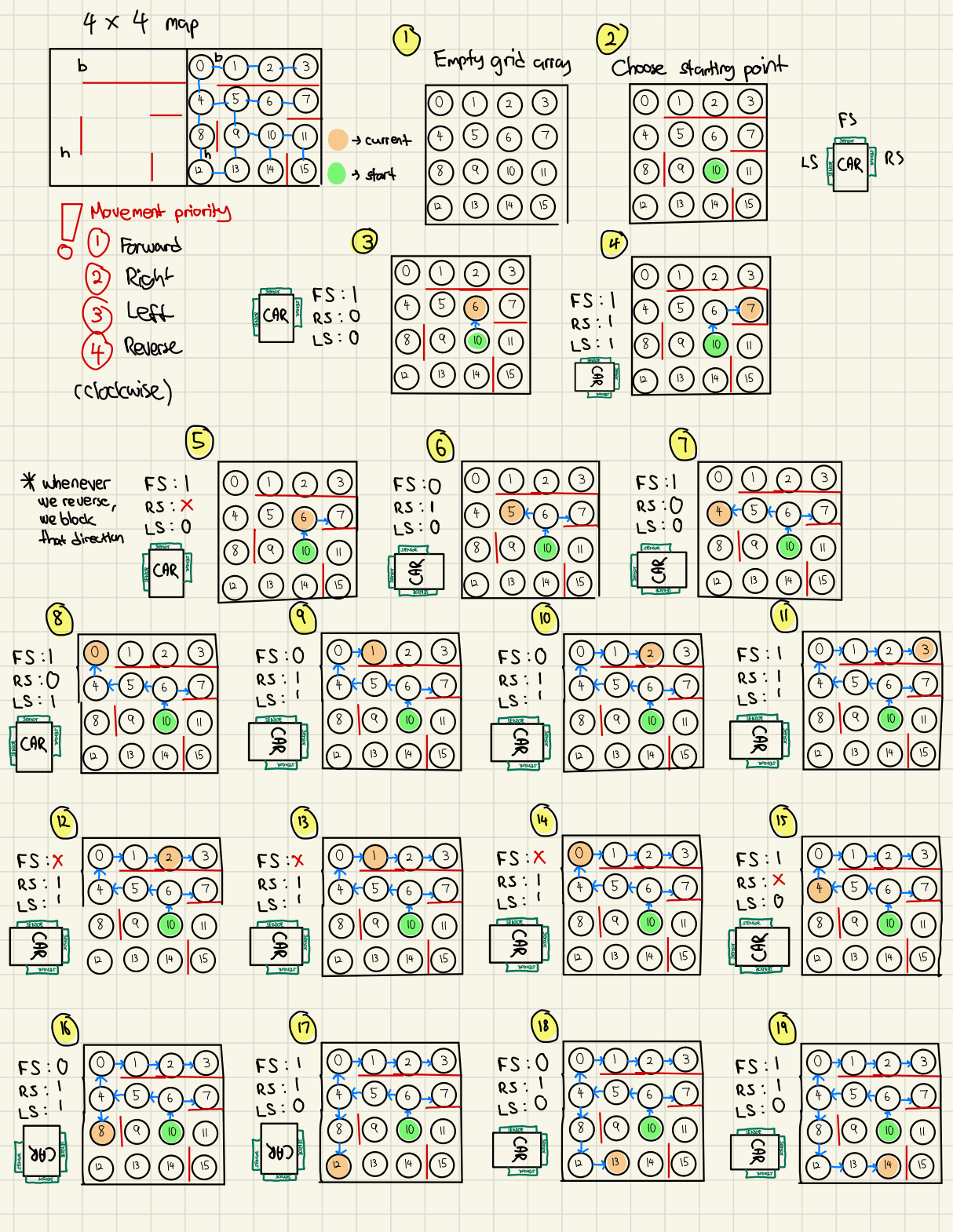
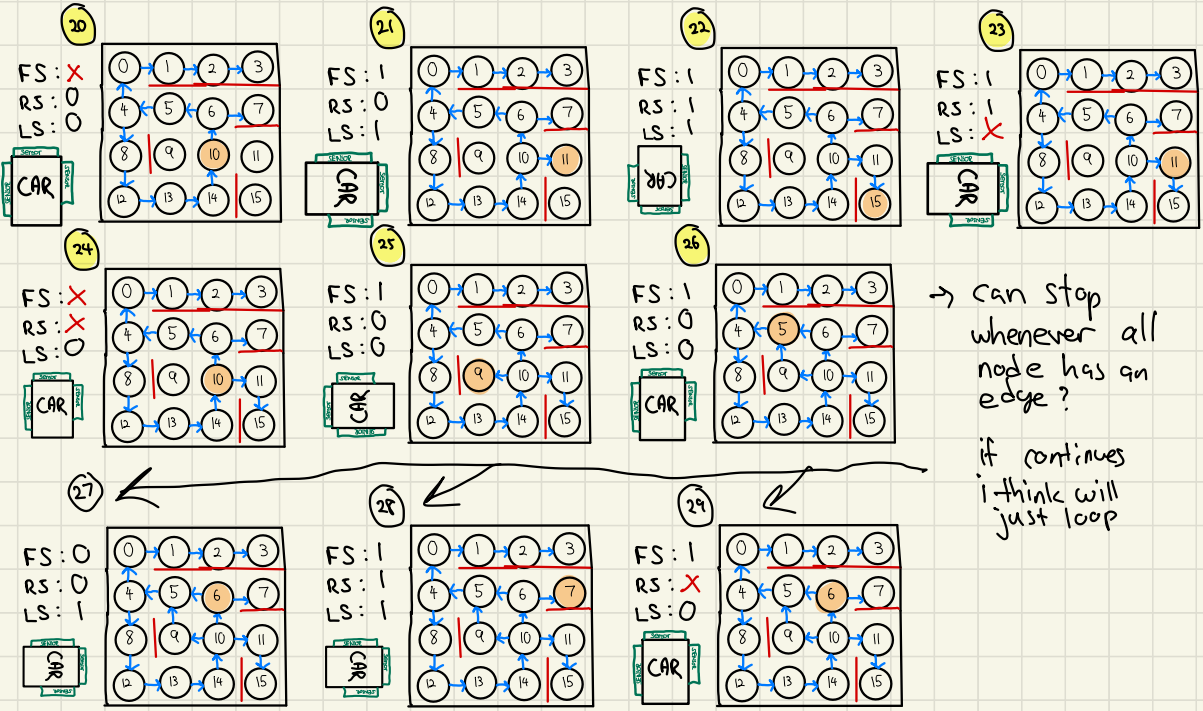

4 x 4 map
b
h
→ current
→ start
1
Empty grid array
2
Choose starting point
FS
LS
CAR
RS
Movement priority
1 Forward
2 Right
3 Left
4 Reverse
(clockwise)
3
FS : 1
RS : 0
LS : 0
4
FS : 1
RS : 1
LS : 1
5
* whenever we reverse, we block that direction
FS : 1
RS : X
LS : 0
6
FS : 0
RS : 1
LS : 0
7
FS : 1
RS : 0
LS : 0
8
FS : 1
RS : 0
LS : 1
9
FS : 0
RS : 1
LS : 1
10
FS : 0
RS : 1
LS : 1
11
FS : 1
RS : 1
LS : 1
12
FS : X
RS : 1
LS : 1
13
FS : X
RS : 1
LS : 1
14
FS : X
RS : 1
LS : 1
15
FS : 1
RS : X
LS : 0
16
FS : 0
RS : 1
LS : 1
17
FS : 1
RS : 1
LS : 0
18
FS : 0
RS : 1
LS : 0
19
FS : 1
RS : 1
LS : 0

If reaches back starting point, block direction that it went before



→ can stop whenever all node has an edge?

if continues i think will just loop

* how to define grid?
  - maybe we can track distance travelled
    e.g. 1 grid length = 4cm
  - have to measure actual board.

* Assumed reversing is either reverse right or reverse left.

* we will only block sensor data, if we reversed or reach starting point

● → NULL

X → edges

edges Matrix → same concept used for Barcode & Humps