**Data**

Public class Kit{

KitStatus KS

List<Part> partsInKit

…

}

enum KitStatus{

AwaitingPickup, PickedUp, PlacedOnStand, Assembled, MarkedForInspection, AwaitingInspection, Inspected, Shipped

}

Map<Kit k, Int destination> ReceivedKits

Int numKitsToMake

//Shared data with KitRobot

List<Kit> KitsOnStand

//Prevent collisions (not for v0)

//Shared with PartsRobot

Semaphore AccessKit

KitRobot kitrobot

FCS fcs**Messages**

//From KitRobot

ShippedKit (){

Kits.get(0).KS = Shipped;

}

//From PartsRobot

KitIsAssembled(Kit k){

k.KS = Assembled;

numKitsToMake--;

}

//From FCS

MakeKits(int numKits){

numKitsToMake = numKits;

}

//From KitRobot

HereIsKit(Kit k, int dest){

ReceivedKits.put(k, dest);

}**Scheduler**

// Need to synchronize

If Ǝ k in KitsReceived

call PlaceKit(k)

Ǝ k in KitsOnStand ϵ

k.KS = Shipped

//Always the 0th kit

KitsOnStand.remove(k)

if(KitsOnStand[1] = null || KitsOnStand[2] = null)

(KitsOnStand[1] = null) ? RequestKit(1) : RequestKit(2)

If Ǝ k in KitsOnStand ϵ

k.KS = Assembled

call RequestInspection(k)

if (numKitsToMake = 0)

call FinalizeOrder()

**Actions**

RequestKit(int index){

Position pos = new Position(index);

kitrobot.NeedKit(pos)

}

PlaceKit(Kit k){

Int spot = ReceivedKits.get(k)

ReceivedKits.remove(k);

KitsOnStand.set(spot, k);

k.KS = PlacedOnStand;

}

RequestInspection(Kit k){

kitrobot.MoveKitToInspectionArea(k);

}

FinalizeOrder(){

fcs.OrderFinished();

// Don’t call statechanged() after // this

}

//This agent has no associated //DoXXX animations