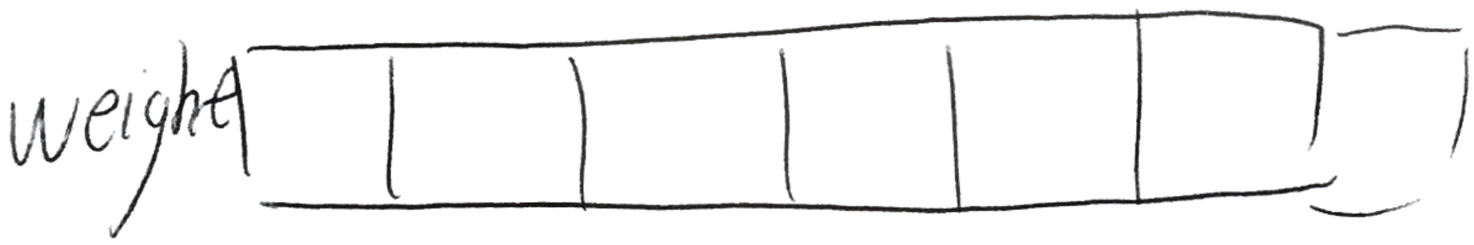
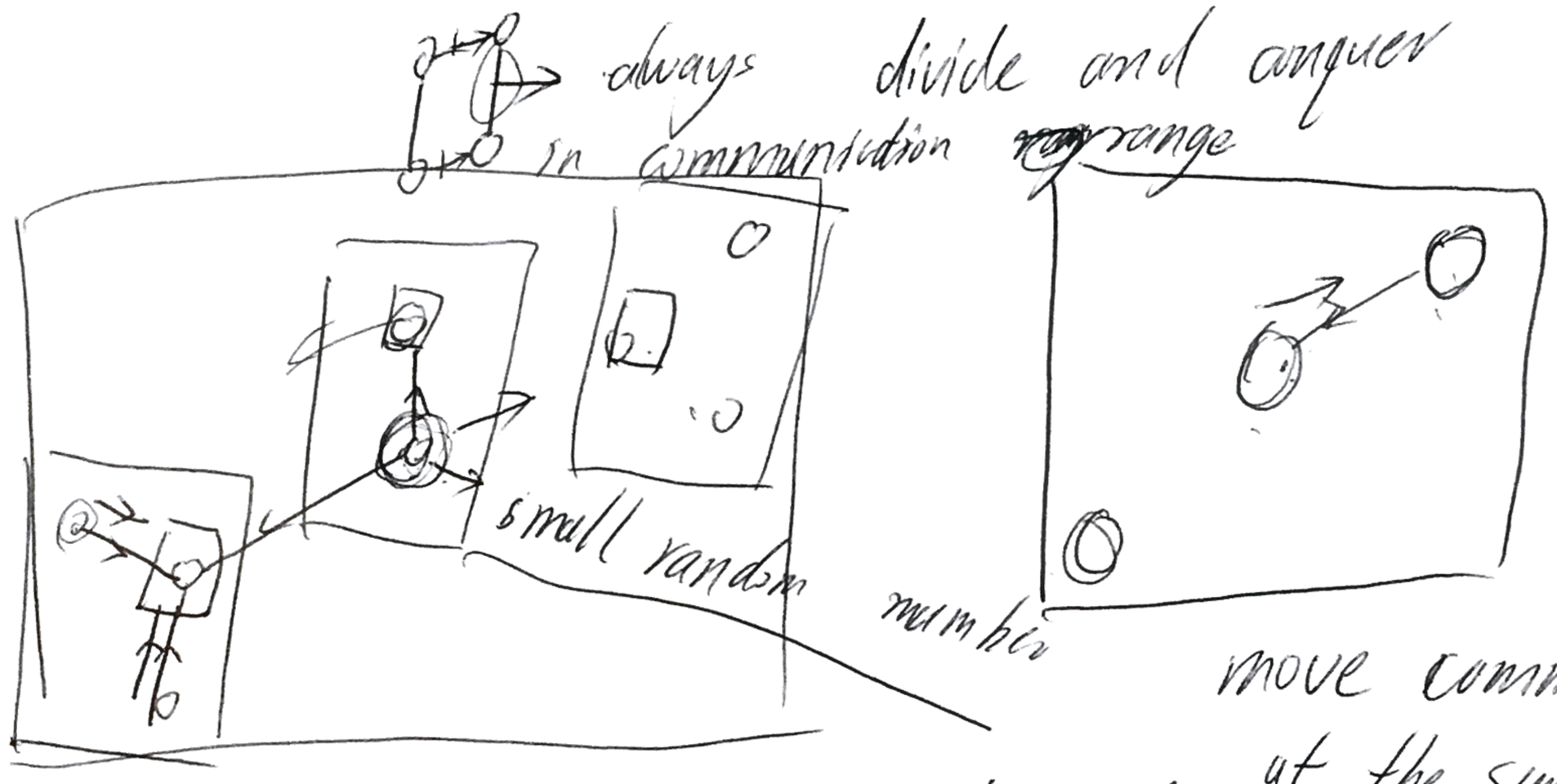
1. get geometric center of a group of robot



↓

points (robots) with higher weight → centroid



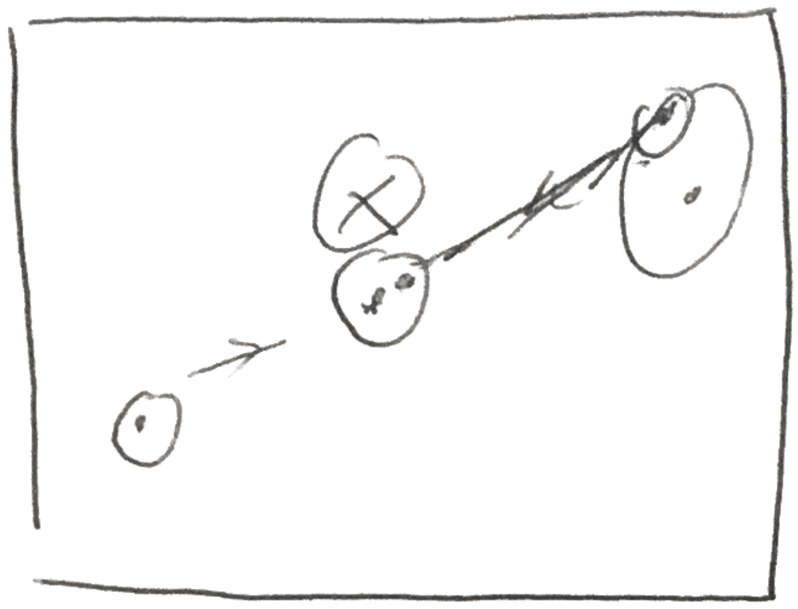
① calculate weight; ← # of pairs at the same time/same

② center robot (not move / fix) direction

③ none-centroid robots move towards → centroid.

④ ending condition RSSI > threshold of communication range.

⑤



5. ① pairs in neighboring group

② pick the group with largest pairs

↓

③ fix that group and move other groups according to the DOF from other group robots

↓