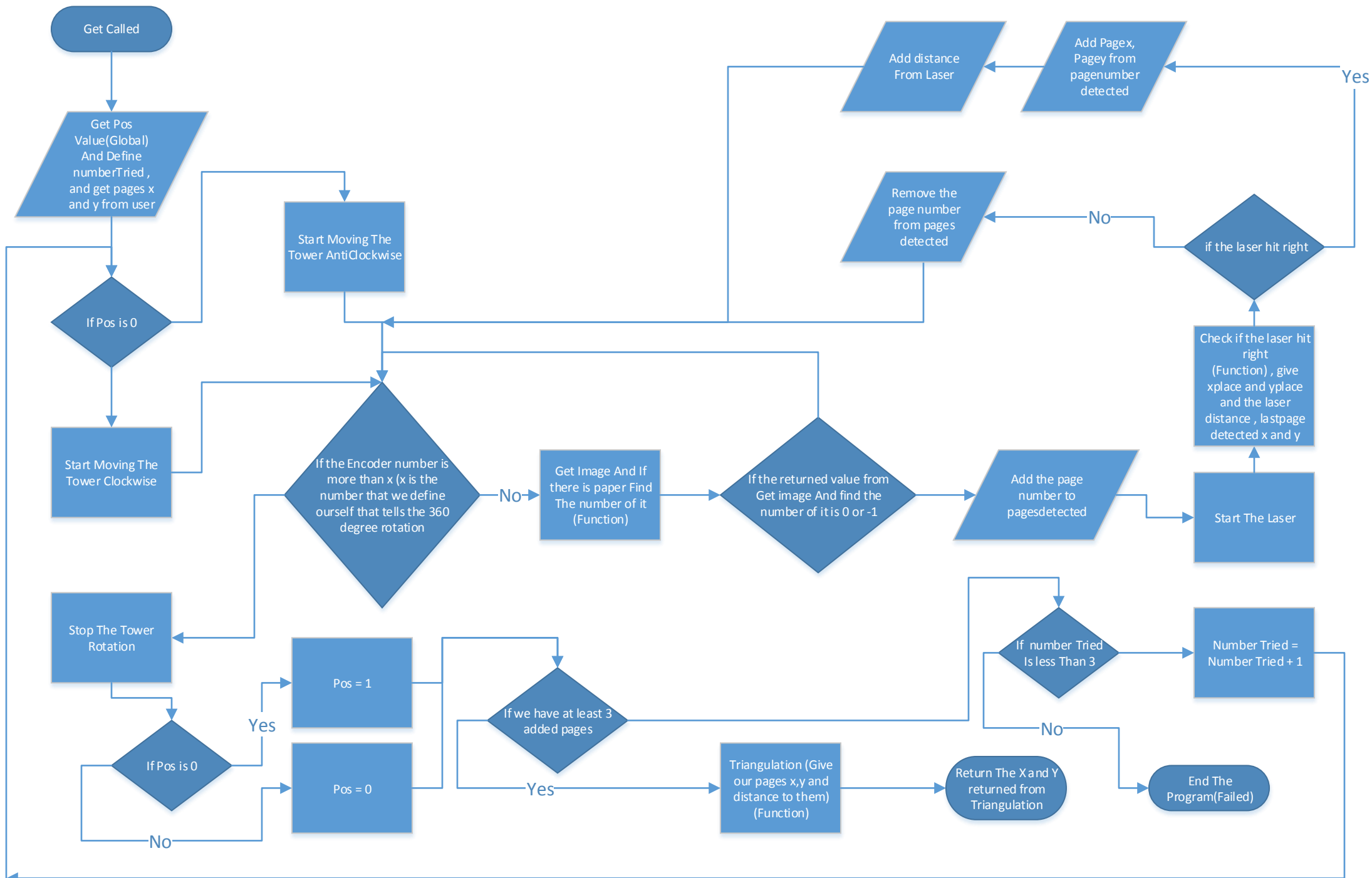
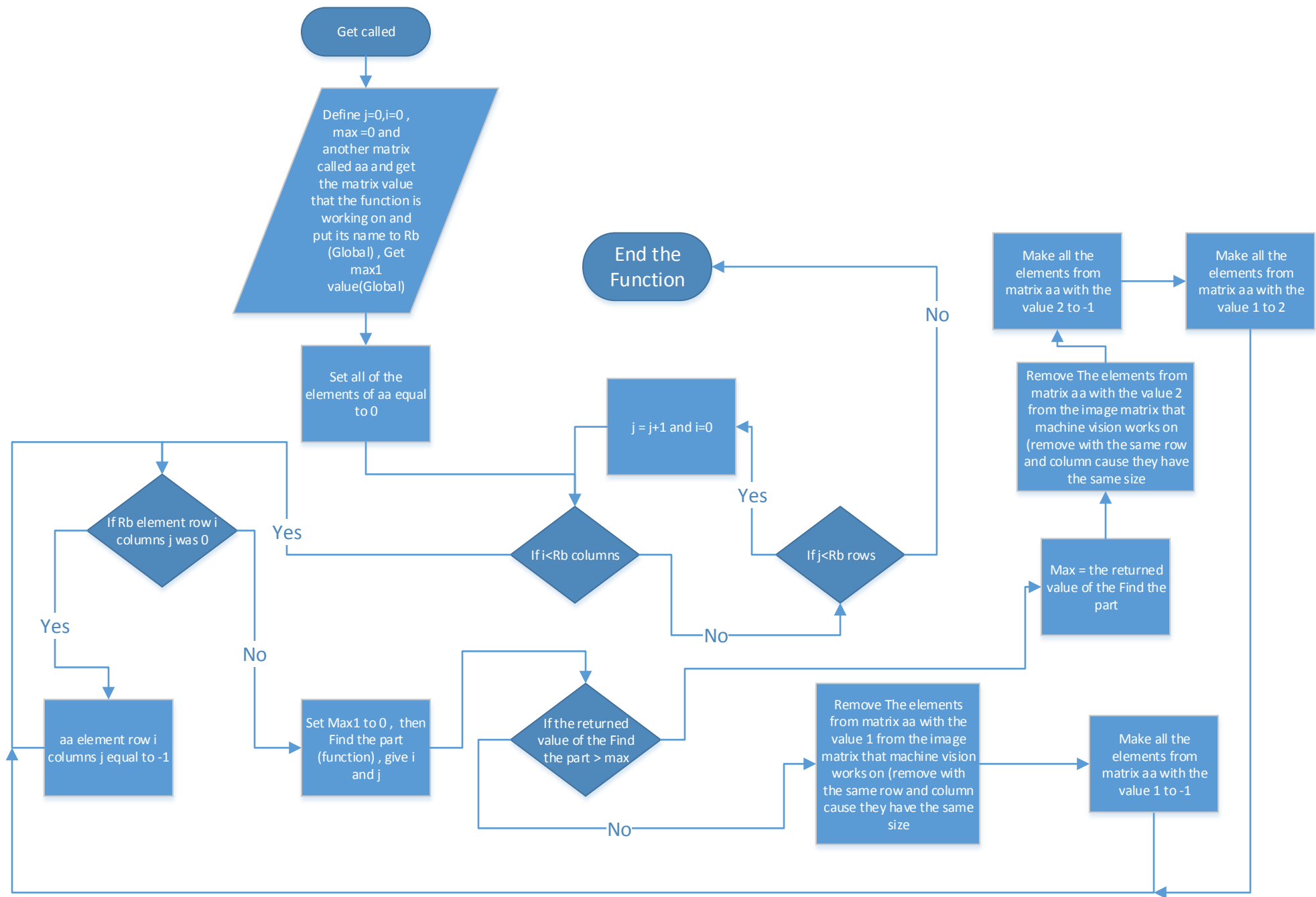


The Main

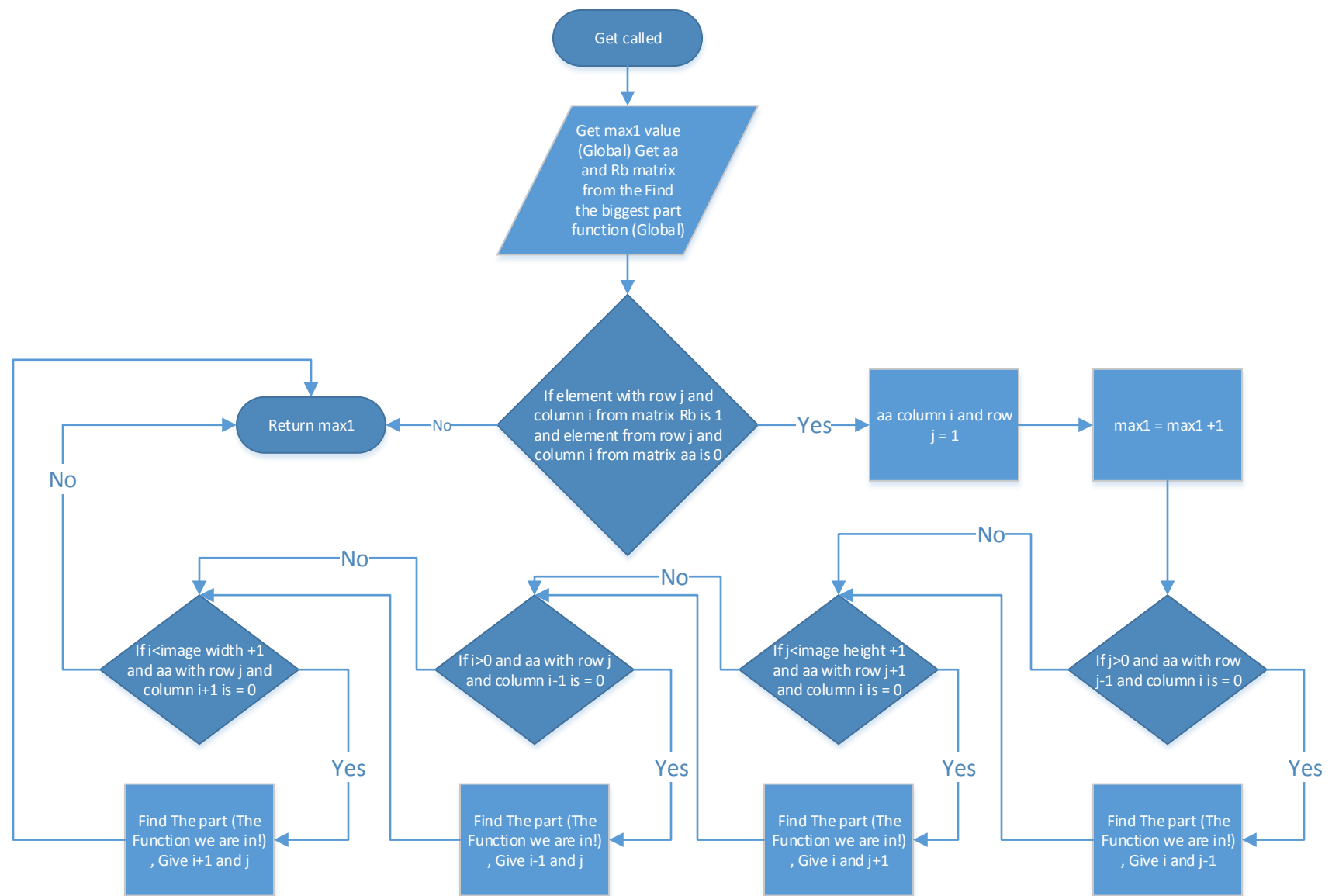


Find our Position (Function) , Returns X and Y ,Gets Xplace and Yplace

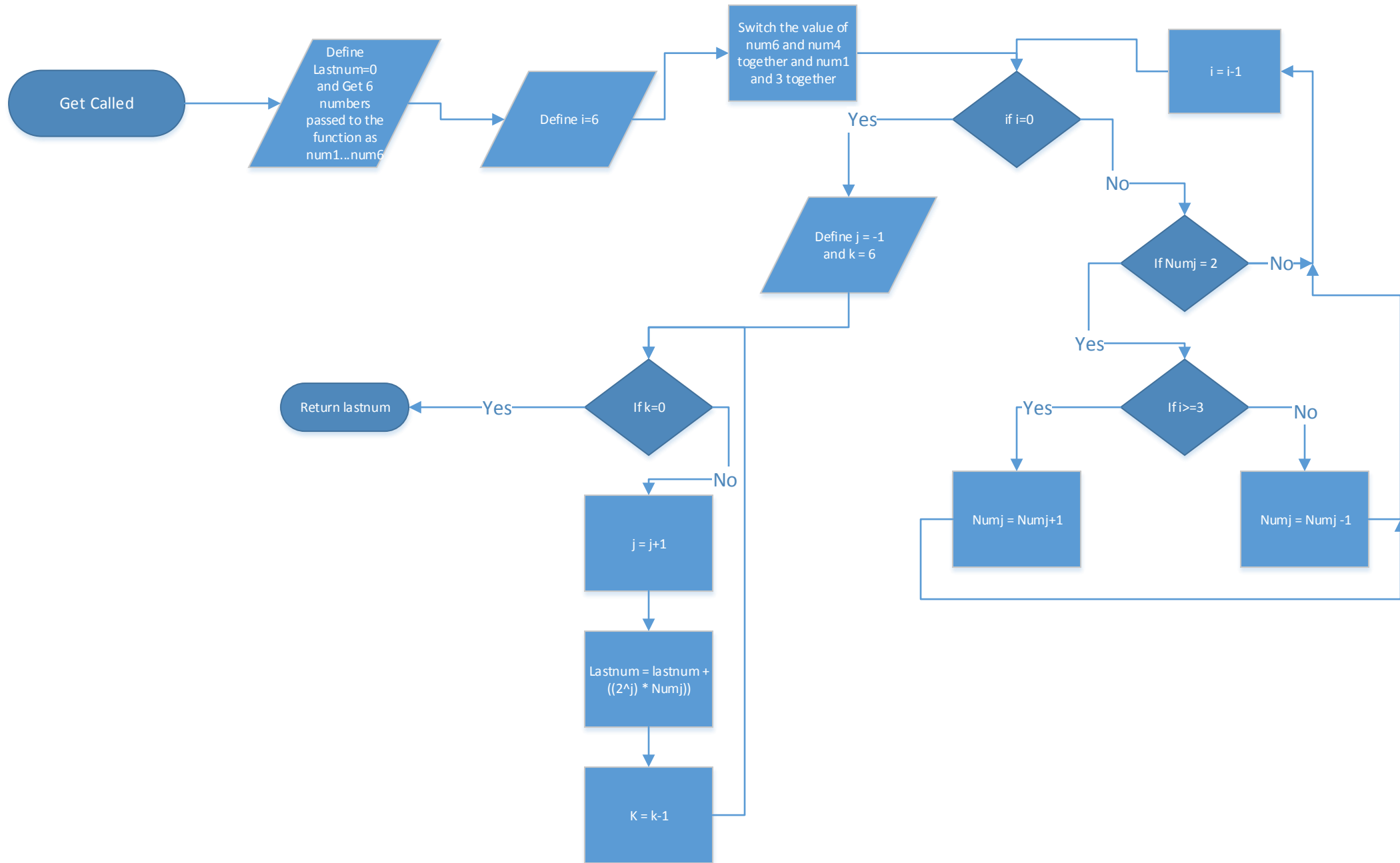




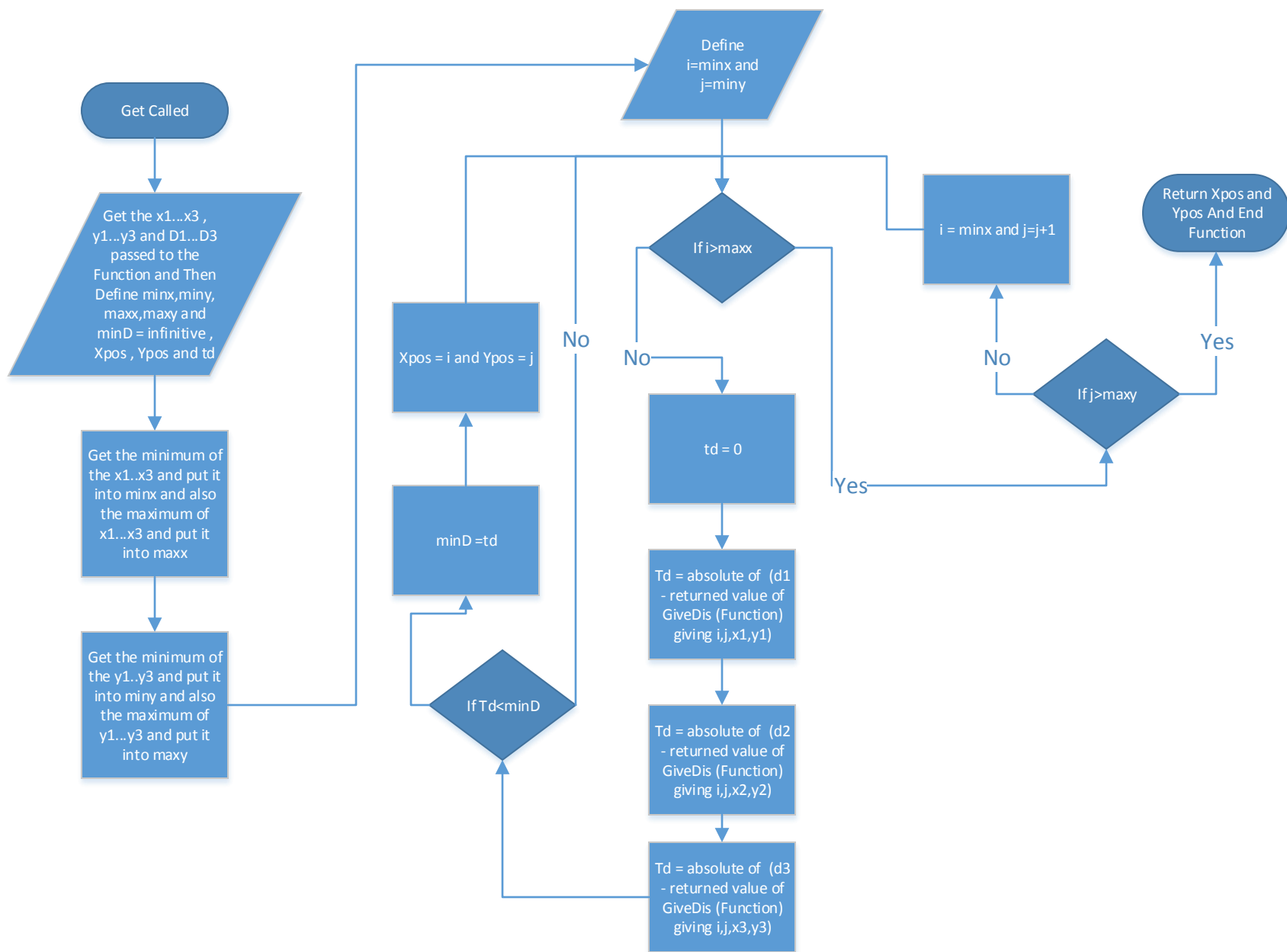
Find The biggest part in matrix that the value of them are 1 and make other matrix values equal to 0 (Function) , Effects the matrix that machine vision works on



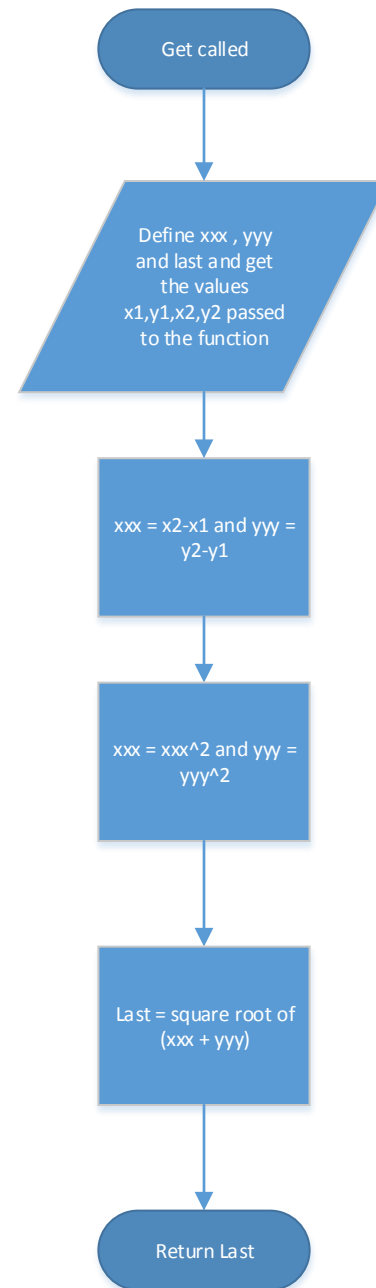
Find the Part (Function) , gets i and j , returns size of the part , used as recursive,  
works on the same matrix called aa and Rb matrix Find the biggest part uses



Turn to base 10 (function) , get 6 numbers , returns num

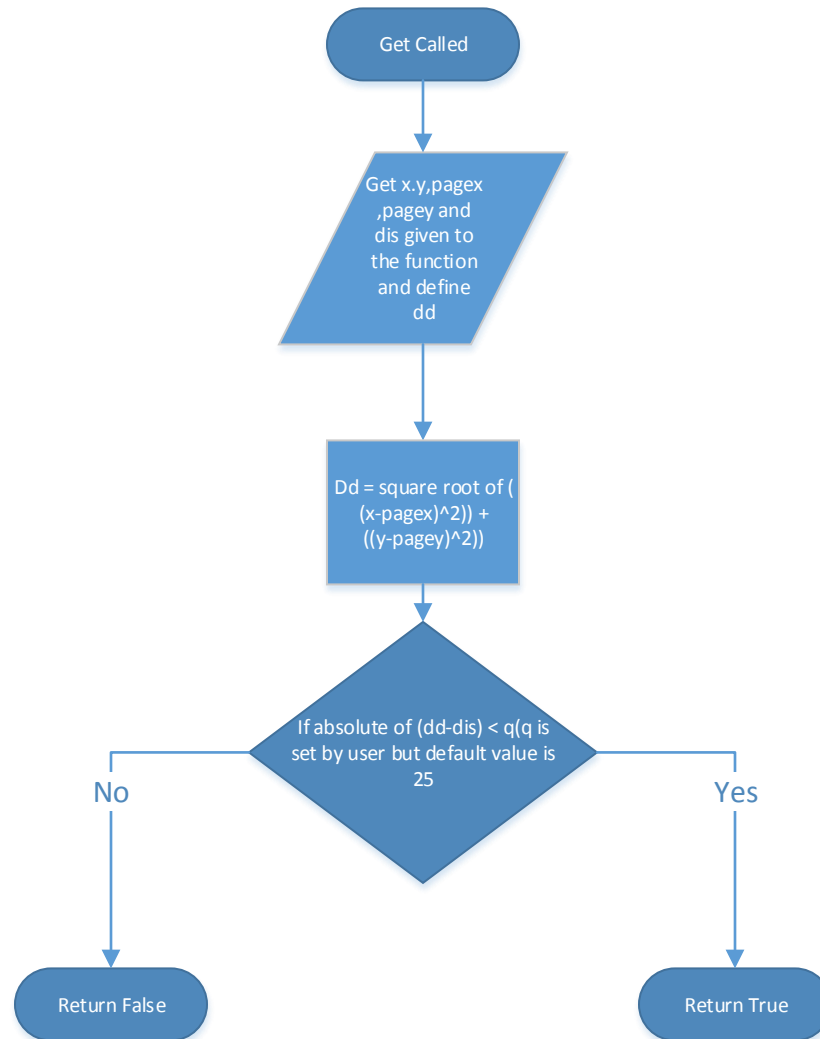


Triangulation (function) , returns x and y , Gets 3x , 3y and distances(d1 is for x1 and y1 and so on)

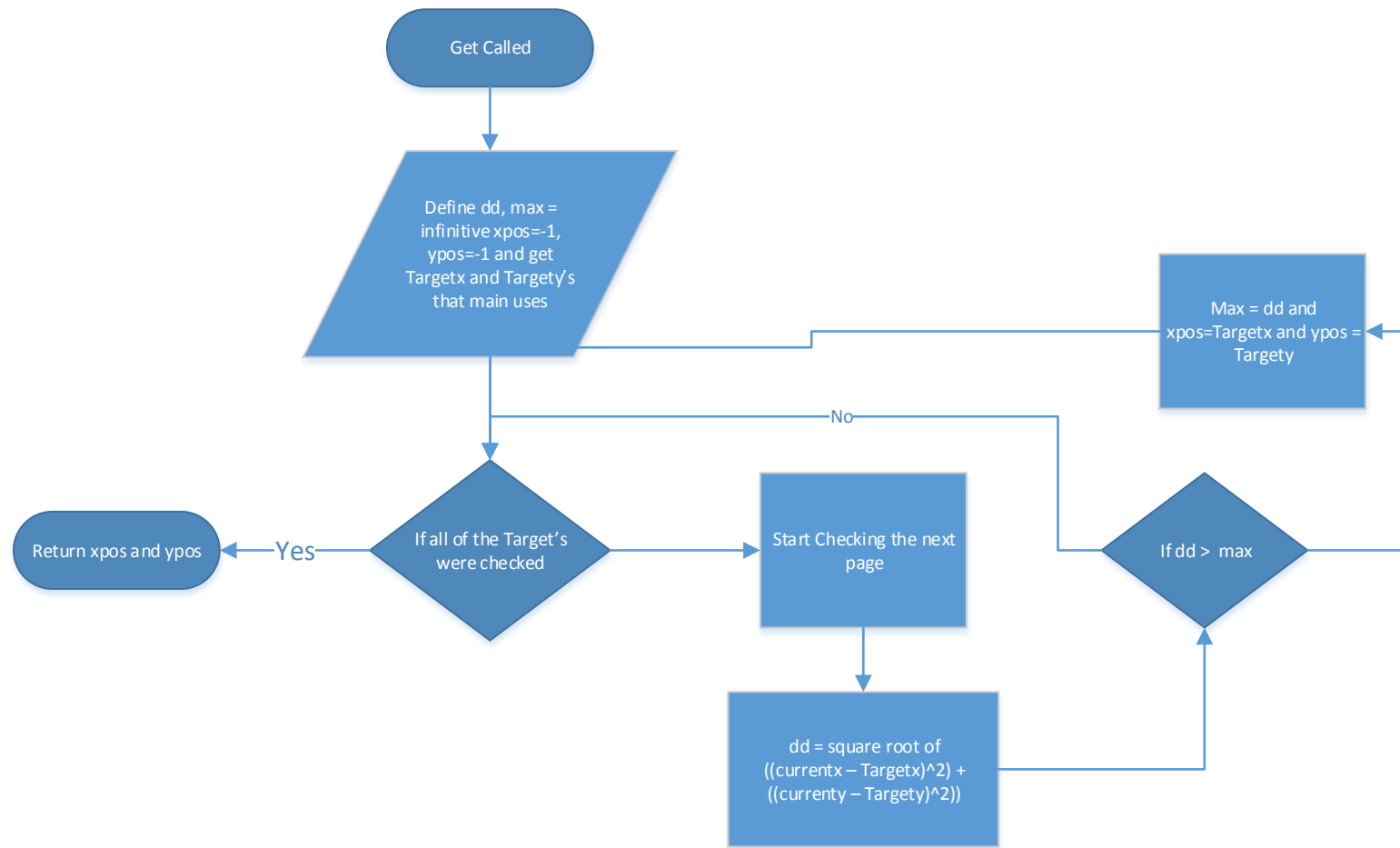


GiveDis (function) , returns Dis , Gets x1,y1,x2,y2

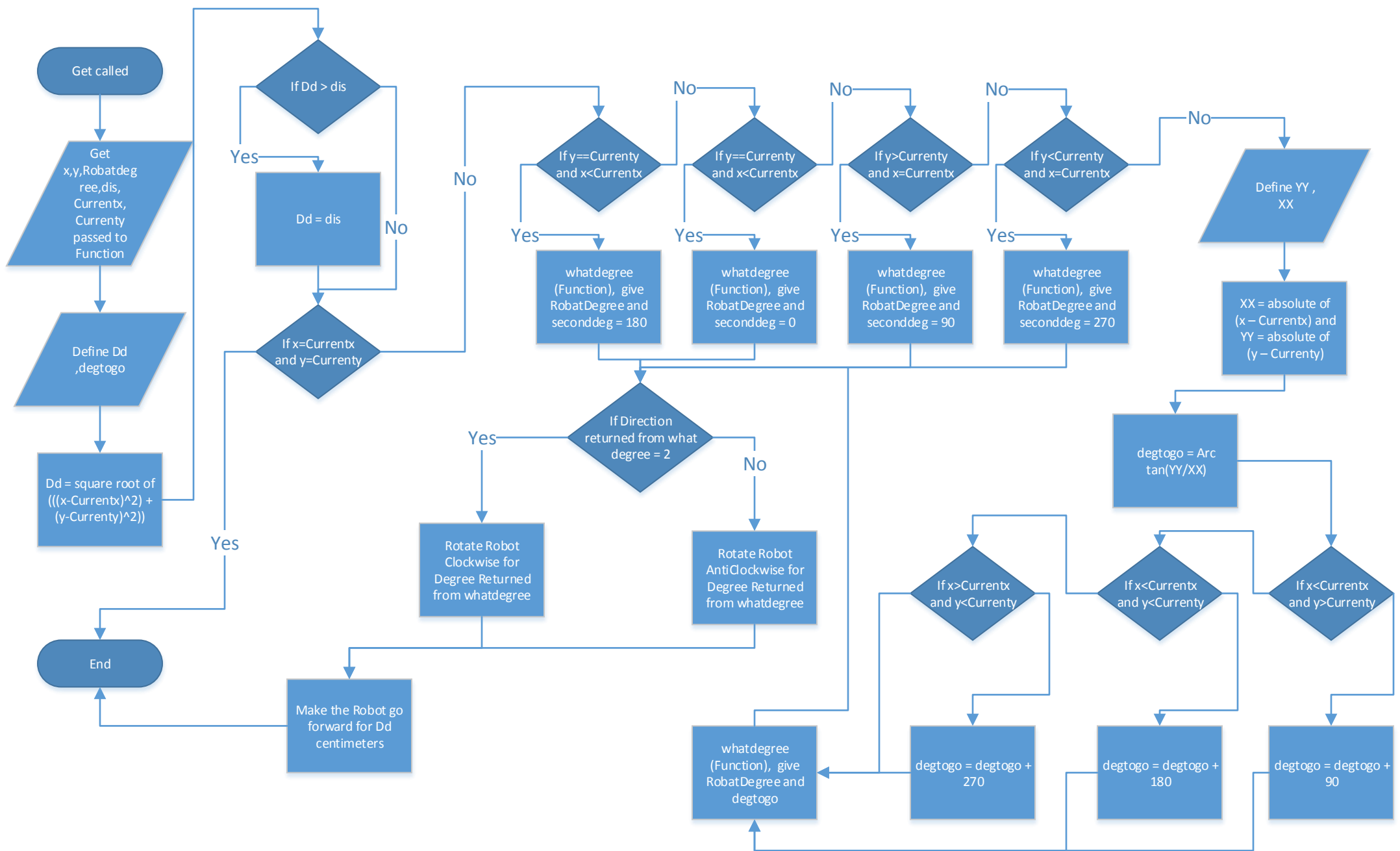




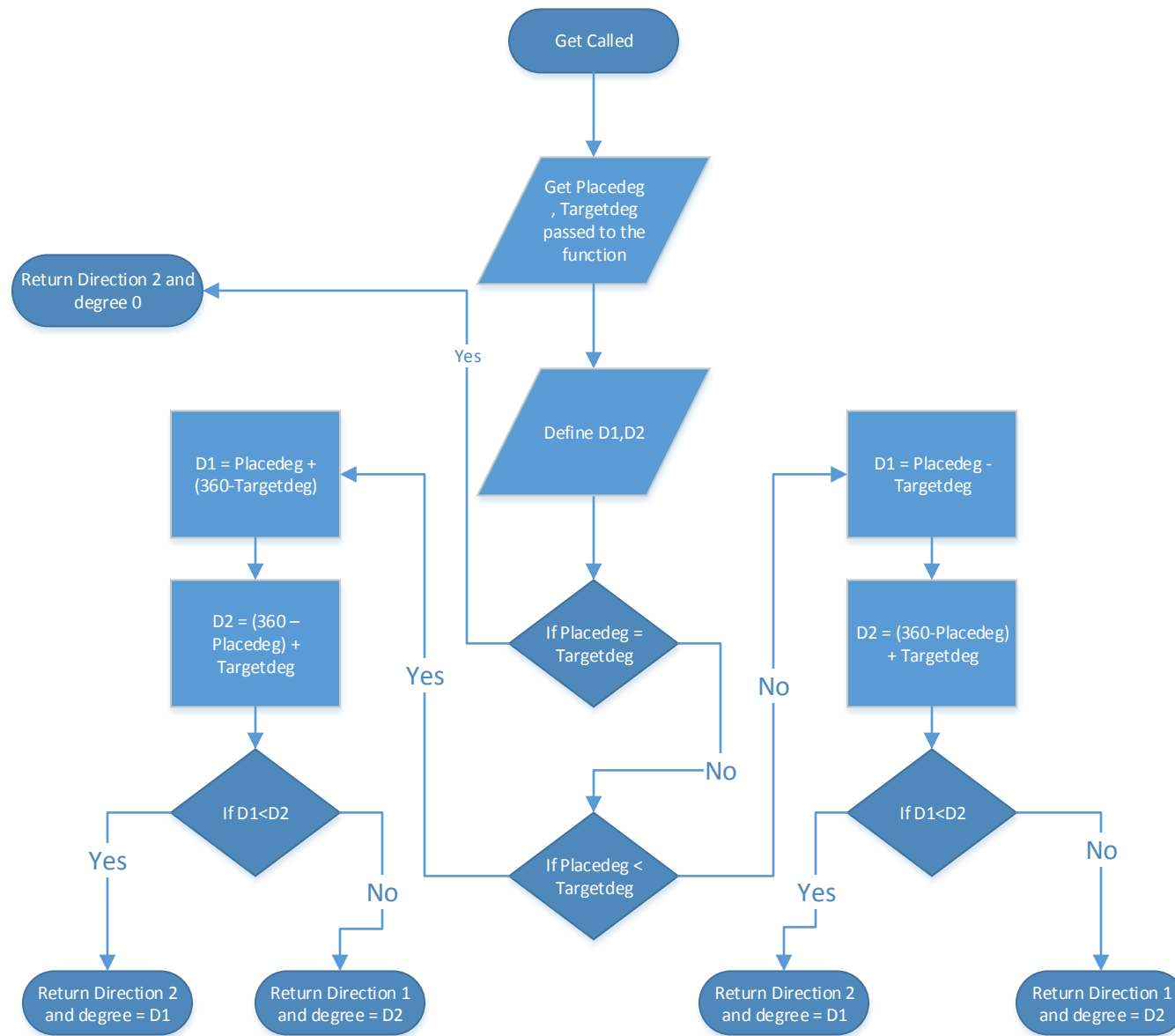
Check if The laser hit right (function) , returns True of false , Gets x,y,dis,pagex,pagey



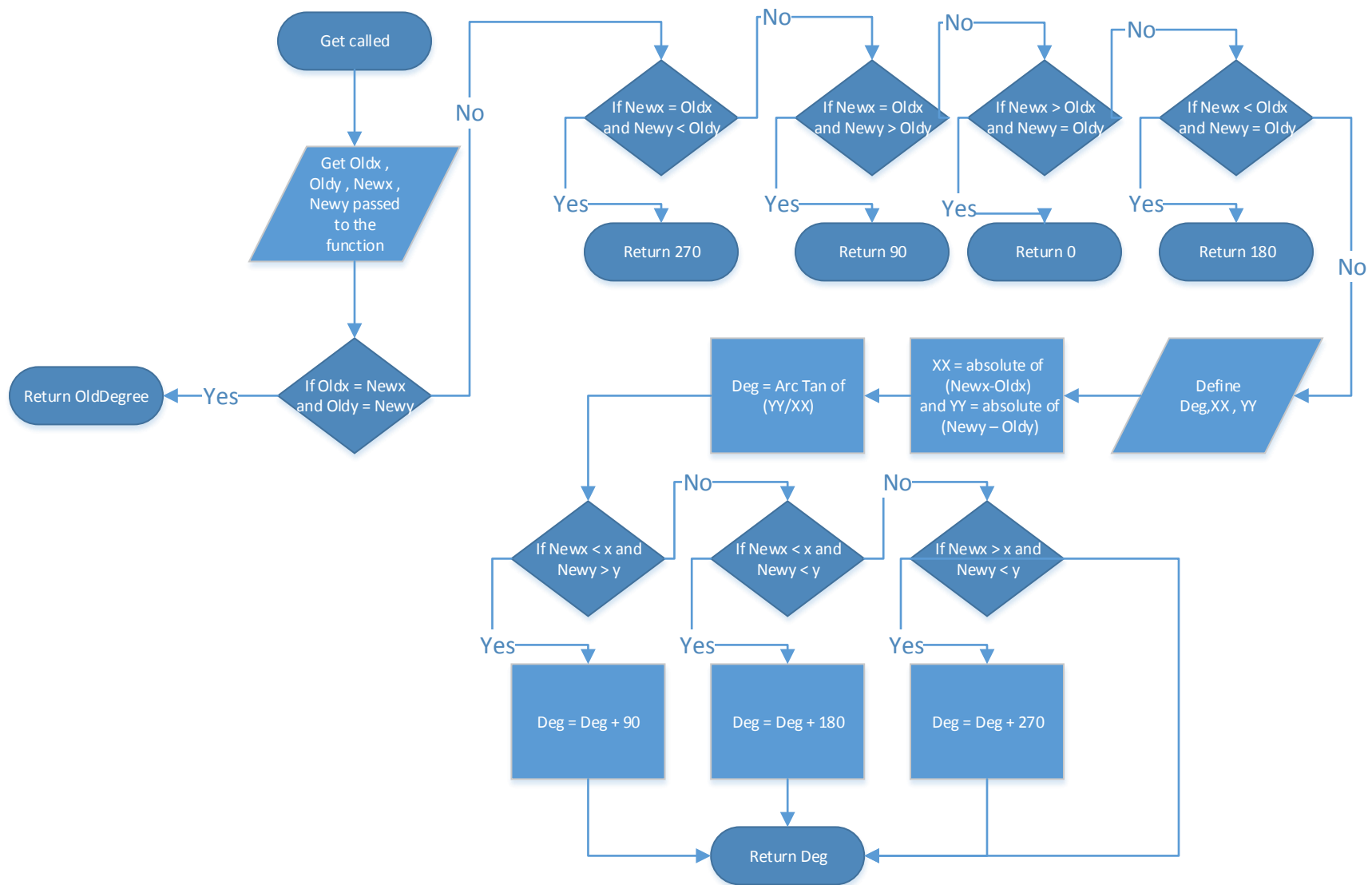
Find The Best Target To go (Function) ,get currentx  
and currenty uses Targetx and Targety Main uses



Go To The target Place , gets x,y,Robatdegree,dis ,CurrentX ,CurrentY , Moves The robot to wanted place



What Degree(Function) , Gets Placedeg , Targetdeg , Returns Direction and degree



Fix Degree (Function) , Get Oldx , Oldy , Newx , NewY , Olddegree , returns Degree