**Pseudo Code for ShootingService**

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**InitShootingService**

*Takes a priority number, returns True*

Initialize the MyPriority variable with the passed in parameter

Set the current state to Waiting2ShootState

Set the C servo to go to the middle position

Set the shooting servo to be in the up position

End of InitCaptureCityService

**PostShootingService**

*Takes an event to post, returns True if event was posted*

End of PostCaptureCityService

**RunShootingService**

*The EventType field of ThisEvent will be one of:* *ES\_StartShooting, ES\_TIMEOUT,*

Switch between the current state:

Case: Current State is Waiting2Shoot

If there is an ES\_StartShooting event

Set the shooting servo to the down position

Set next state to ShootingServoDownState

Start the shooting timer

End case

Case: Current State is ShootingServoDownState

If there is a shooting timer timeout

Set the shooting servo to be in the up position

Set the current state to ShootingServoUpState

Start the shooting timer to go to next state

EndCase

Case: Current State is ShootingServoUpState

If there is a shooting timer timeout

Set the C servo to be in the down position

Set the current state to CServoDownState

Start the shooting timer to go to next state

EndCase

Case: Current State is CServoDownState

If there is a shooting timer timeout

Set the C servo to be in the up position

Set the current state to CServoUpState

Start the shooting timer to go to next state

EndCase

Case: Current State is CServoUpState

If there is a shooting timer timeout

Set the C servo to be in the middle position

Set the current state to CServoMiddleState

Start the shooting timer to go to next state

EndCase

Case: Current State is CServoMiddleState

If there is a shooting timer timeout

Set the current state back to Waiting2ShootState

Pos ES\_BallShot to MasterSM (Navigation will respond)

EndCase

End of RunShootingService