Our project is about a squad of footmen that encounter a skeleton (the enemy). For the first part, we decided to make the squad walk up to a point, where they meet the skeleton and they start fleeing, and the skeleton pursuits them. Since for the first part there were no sensors implemented, we scripted the meeting of the footmen and the skeleton, i.e. we made the footmen go to a certain point, made the skeleton go near that point and placed them in such a way that they will reach there at the same time.

The movement of the footman squad has been implemented with SteerForPoint, in order to get to the meeting point, and SteerForCohesion, in order to make them steer as a team (flock). They also use SteerForSphericalObstacles in order to avoid trees (the obstacles in our environment). We have many trees in our environment we couldn’t make them be detectable by default, so we had to manually add an invisible detectable object inside them. For this reason, only some trees around the meeting point are detectable (and avoidable). In order to keep the footmen inside the area with detectable trees, we added a SteerForTether script that makes them stay within a distance of an interest point.

In order to flee from the skeleton, we used a modified SteerForTether Script. We have tried to use SteerForEvasion, but that script is made to avoid a collision with another character, not to run from it. Since SteerForTether is made to keep within a maximum distance from a point, it is easy to see that the reverse would be to keep a minimum distance away from a point. Thus, we changed the script and created SteerForReverseTether. Then we changed the footmen control script so that it constantly updates the tether point of SteerForReverseTether to be the skeleton’s location.

The skeleton’s movement is implemented using SteerForPoint in order to reach the meeting point and then it uses SteerForPursuit in order to run after the Red footman.