



neighbours: nat

obstacle: Position



Movement [cycleDef = (cycle==1)]

Inputs

Outputs

ⓘ MovingHwE
ⓘ SensingHw

Ⓜ MovingHwRS

π lv: real = 0, av: real = 180, MB: real = 4, alpha: nat = 1, cWait: real = floor(random()*360/av), cTurn180: real = floor(180/av), cRandom: real = floor(random()*360/av)
 \times n: nat, p: Position, turned: boolean
 ⌚ MBC

