**decision.py**

To the decision module was added the ability of handling rocks. If the rock is not too close, the Rover tries to move slowly, but if it is too close, the Rover stops.

A new Rover mode ’stuck’ is defined. In this mode the Rover is steered, and tried to move forward.

**drive\_rover.py**

For the rock detection there were added two variables (*rocks\_angles*, *rocks\_dists*) to the Rover state.

The missing action step was added following the comment “# The action step! Send commands to the rover!”

**perception.py**

The original *color\_thresh* function is used only for the terrain coordinates. Other functions were created and used for the rock (*rock\_thresh*) and obstacle (*obstacle\_thresh*) coordinates. While the original function checks the above condition, the *obstacle\_thresh* checks the below condition, and the *rock\_thresh* checks inside a given interval of the *rgb\_thresh* values.

In the *perception\_step* function the needed steps are processed for the rocks, obstacle and terrain too. In additionally are calculated the distance and angle of the rocks, which are used for rocks detection.