Take in User Input

Move the bot forwards based off the centimeters given in user input if sensor trip send to UART and backup 15cm

Send command back to UART after processing data (command ex. w10, s20, d45, a90, t, p)

Move the bot backwards based off the centimeters given in user input

Rotate the bot counter clockwise based off the degrees given in user input

Rotate the bot clockwise based off the degrees given in user input

Send Done to UART after completed

Send Done or what sensor was tripped to UART after completed

Send the information about the found object to the UART if there is any

Send Done to UART after completed

Send Done to UART after completed

Go to main.c

Run the scan (IR, PING, and SERVO)

Go to movement.c

Go to movement.c

Go to movement.c

Go to movement.c

Send data that you have received back to the USER

USER

Send Done to UART after completed

Go to open\_interface.c

First char of input is p

First char of input is d

First char of input is a

First char of input is s

First char of input is w

First char of input is t

Turn Right

UART

Flash Power Light to signify reaching endzone

Load and Play a song

Turn Left

Move

Backward

Perform a Scan

Move Forward

Endzone has been reached

UART