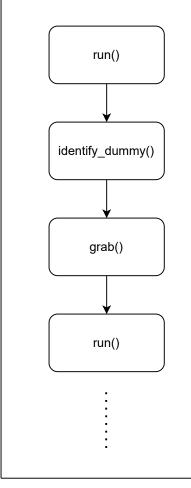
run() initializing !(i < repeat) for (int i; i < repeat; i++) i < repeat sensors readings while true stop? false true errors? release all motors false delay() error_callback() calculate new motor speeds update motor speeds end while callback() release all motors

Algorithm



Algorithm

The overall algorithm is a chain of functions corresponding to actions that robot will take, of which **run()** is the most important. **run()** is shown in the left flowchart.