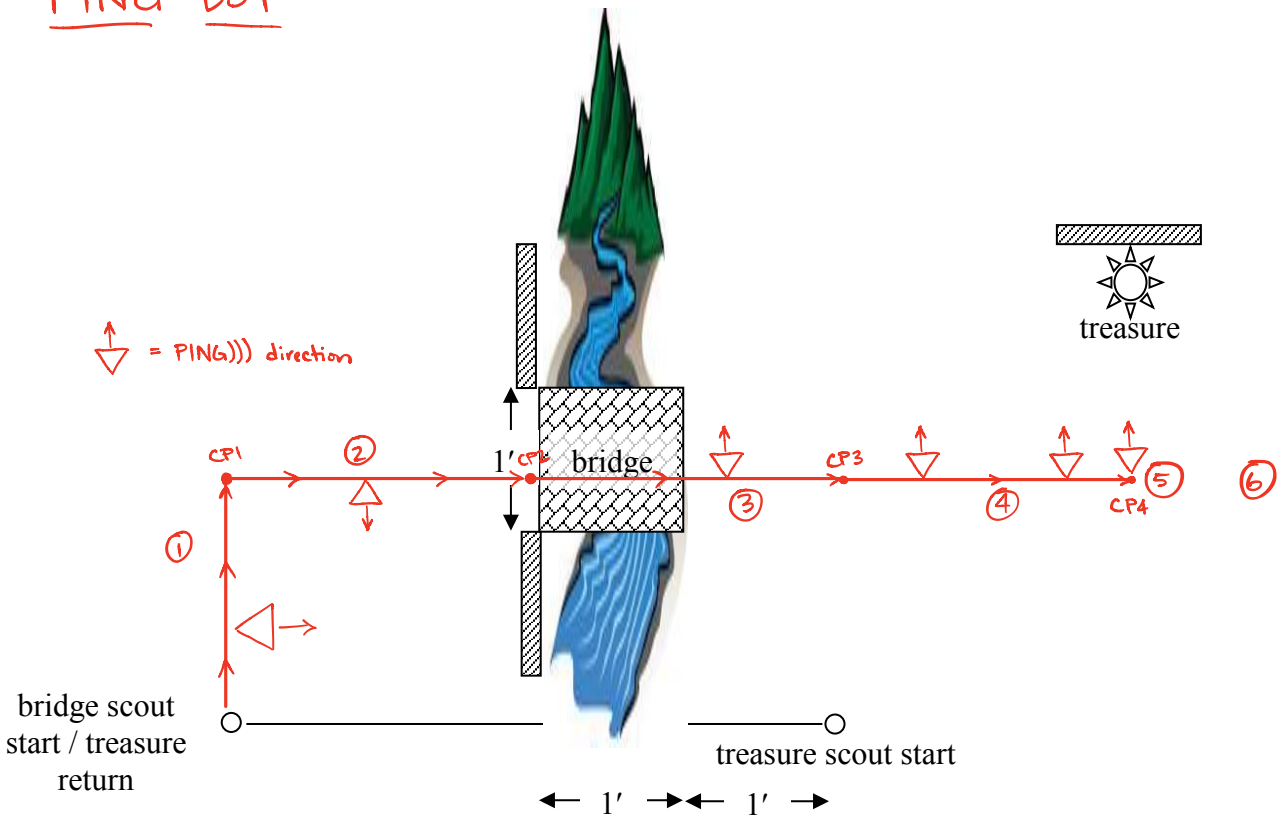
PING BOT



① - Orient PING))) to the right
- Drive forward
  a. Count encoder passes
  b. Monitor PING for change in distances
    ↳ If distance changes greater than error threshold:
      Save encoder count plus # of encoder counts in 6"
      Convert encoder counts to in. & save value to distanceArray[0]
      Else { }
- Drive forward 6"
- Turn 90° right

② - Do not change PING))) orientation
- Drive forward
  a. Count encoder passes
  b. Monitor PING for change in distances
    ↳ If distance changes greater than error threshold:
      Save encoder count
      Convert encoder counts to in. & save value to distanceArray[1]
      Else { }

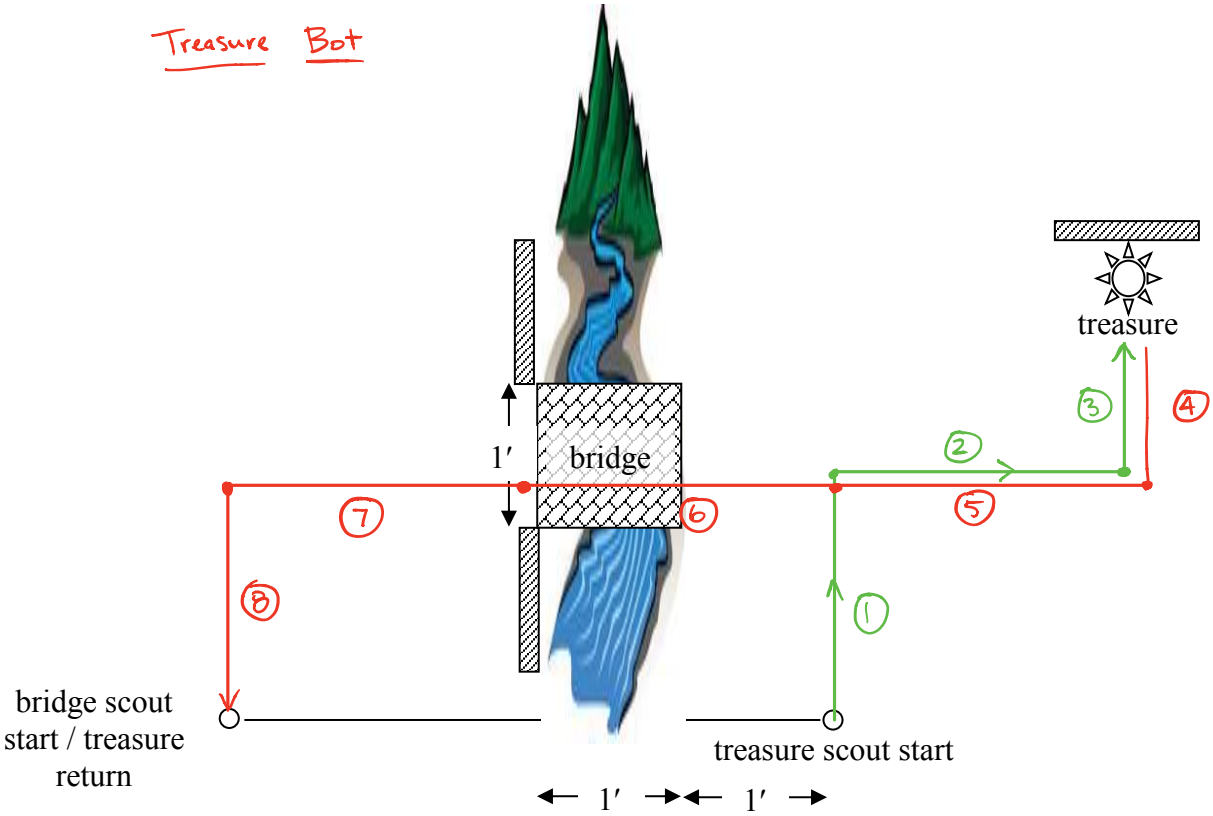
③ - Orient PING))) to the left
- Drive forward 2 ft

④ - Drive forward
  a. Count encoder passes
  b. Monitor PING for change in distances
    ↳ If distance changes greater than error threshold:
      Save encoder count
      Convert encoder counts to in. & save value to distanceArray[2]
      Else { }

⑤ - Read distance in in.
- Save distance to distanceArray[3]
- Reverse course to return to start

⑥ - TX distanceArray[] to grabber bot

Treasure Bot



① - Receive distance Array [ ]
- Open grabber
- Move forward by distance Array[0]
- Turn 90° CW

② - Move forward by distance Array[2]
- Turn 90° CCW

③ - Move forward by {distance Array[3] - 6"}
- Close grabber

④ - Move backward by {distance Array[3] - 6"}
- Turn 90° CCW

⑤ - Move forward by distance Array[2]

⑥ - Move forward 2 ft.

⑦ - Move forward by distance Array[1]
- Rotate 90° CCW

⑧ - Move forward by distance Array[1]
- Halt