

**Q1c.):**

```
Boundary_map = cannyEdgeDetection(tennis_court_map);
Save_to_robot(Boundary_map);    # Use the shape of court to create coordinate system
While(1):
    Read(image_frame);
    [X,Y,Z] = DPM(tennis_ball);
    If Z == 0:
        moveToLocation(X,Y,Z)  #move to ball location when ball reach ground
        If obstacle_Detect() == true:
            Avoid();
        If faceDirection() == [X,Y,Z]:    #arrived ball's location
            grabObjectAtLocation(ball's location);
            moveToLocation(servers location);
```