**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);