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bluebox=[draw=blue!50,fill=blue!20,anchor=south west]
orangebox=[draw=orange!80!black,fill=orange!80,anchor=south west]
component=[bluebox,drop shadow=opacity=0.25,minimum
width=2.6cm,minimum height=1.6cm] speccomp=[orangebox,drop
shadow=opacity=0.25,minimum width=2.6cm,minimum height=1.6cm]
touchcomp=[component,draw=orange!80,very thick]
semitcomp=[touchcomp,dashed] subcomp=[bluebox,draw=blue!40,minimum
width=1.3cm,minimum height=0.6cm] senscomp=[bluebox,drop
shadow=opacity=0.25,minimum width=2.6cm,minimum height=1.2cm]
senscomp=[senscomp,draw=orange!80,very thick] resource=[bluebox,rounded
corners,minimum height=1.0] compsign=[draw=blue!50,fill=blue!20]
compsignorange=[draw=orange!50!black,fill=orange!80]
ccs=[\i=latex,-o,thick,color=blue!50] cce=[\i=latex,-,thick,color=blue!50]
conn=[\i=latex,thick,color=blue!50] conncirc=[draw=blue!50,fill=blue!50]
(naomanasim) [touchcomp] at (0,4.0) ; (naomotion) [touchcomp] at (4.6,7.0)
;(naomotionact)[subcomp]at(4.6cm + 1.2pt,7cm +
1.2pt)act;(naomotionnav)[subcomp]at(4.6cm + 1.25cm + 1.2pt,7cm +
1.2pt)nav;(skiller)[speccomp]at(11.6,4.6);(agent)[speccomp]at(11.6,2.1);(fvbase)[semitcomp]at(0,0.6);(odometry)
6.2cm,rotate = 90]at(10.4,0)worldmodel;(image)[resource,minimumwidth =
1.6cm,rotate = 90]at(3.8,0.6)Image;(network)[resource,minimumwidth =
2.6cm,]at(11.6,0)Network;
[conn,dashed,thin] (naomanasim.west) .. controls +(0.65,-0.1) ..
((naomanasim.west) + (1.3,0)) .. controls +(0.65,0.1) .. (naomanasim.east);
(naomanasim.north west) node [below right] naomana; (naomanasim.south
east) node [above left] naosim;
(fvbase.north west) node [below right] fvbase; (naoball.north west) node
[below right] naoball; (naolocalize.north west) node [below right] naolocalize;
(naomotion.north west) node [below right] naomotion; (skiller.north west)
node [below right] skiller; (agent.north west) node [below right] agent;
(odometry.north west) node [below right] odometry; (naocampos.north west)
node [below right] naocampos;
[conn,-\i] (fvbase.east) - (image.north); [conn,-\i] (image.south -
naolocalize.south) - +(0.35,0) - (naolocalize.west); [conn,-\i] (image.south
- naoball.north) - +(0.35,0) - (naoball.west);
[ccs] (naoball.east) - +(0.8,0); [cce] ((naoball.east) + (0.8,0)) - (naoball.east
- worldmodel.north); ((naoball.east) + (0.8,0)) node [below,inner
ysep=0.4em] ball pos;
[ccs] (naolocalize.east) - +(0.8,0); [cce] ((naolocalize.east) + (0.8,0)) -
(naolocalize.east - worldmodel.north); ((naolocalize.east) + (0.8,0)) node
(robotpose1)[below,innerysep = 0.4em]robotpose;
[ccs] (odometry.east) - +(0.6,0); [cce] ((odometry.east) + (0.6,0)) -
(odometry.east - worldmodel.north); [conn] ((odometry.east) + (1.2,0)) -
+(0,-2.6) - (naolocalize.north); [conncirc] ((odometry.east) + (1.2,0)) circle
(0.05); ((odometry.east) + (0.8,0)) node
(odomlab)[above,innerysep = 0.4em]odometry;
[ccs] (naocampos.east) - +(0.6,0); [cce] ((naocampos.east) + (0.6,0)) -
((naocampos.east) + (1.1,0)) .. controls ((naocampos.east) + (1.2,0.1)) ..
((naocampos.east) + (1.3,0)) - (naocampos.east - worldmodel.north); [conn]
((naocampos.east) + (0.95,0)) - +(0,-0.8) - ((naolocalize.north) + (-0.4,0.4))
- ((naolocalize.north) + (-0.4,0)); [conncirc] ((naocampos.east) + (0.95,0))
circle (0.05); ((naocampos.east) + (0.5,0)) node [above,inner ysep=0.5em] cam;
((naocampos.east) + (0.5,0)) node [below,inner ysep=0.6em] pos;
[ccs]
(naomotionact.south) - - + (0, -0.38); [cce]((naomotionact.south) + (0, -0.38))
- (naomotionact.south - odometry.north); [conn]((naomotionact.south) +
(0, -0.65)) - +(-1,0) - ((naomotionact.south - odometry.west) + (-1.0,0.1))

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    bluebox=[draw=blue!50,fill=blue!20,anchor=south west]
    orangebox=[draw=orange!80!black,fill=orange!80,anchor=south west]
    component=[bluebox,drop shadow=opacity=0.25,minimum
    width=2.6cm,minimum height=1.6cm] speccomp=[orangebox,drop
    shadow=opacity=0.25,minimum width=2.6cm,minimum height=1.6cm]
    touchcomp=[component,draw=orange!80,very thick]
    semitcomp=[touchcomp,dashed] subcomp=[bluebox,draw=blue!40,minimum
    width=0.8666cm,minimum height=0.6cm] senscomp=[bluebox,drop
    shadow=opacity=0.25,minimum width=2.6cm,minimum height=1.2cm]
    sensstcomp=[senscomp,draw=orange!80,very thick]
    sensstcmp=[senscomp,draw=orange!80,very thick,dashed]
    resource=[bluebox,rounded corners,minimum height=1.0]
    compsign=[draw=blue!50,fill=blue!20]
    compsignorange=[draw=orange!50!black,fill=orange!80]
    ccs=[\i=latex,-o,thick,color=blue!50] cce=[\i=latex,-,thick,color=blue!50]
    conn=[\i=latex,thick,color=blue!50] conncirc=[draw=blue!50,fill=blue!50]
    (kicker) [component] at (0,5.5) ; (navigator) [component] at (0,3.5)
;(navigatoract)[subcomp]at(0.0, 3.5)mot; (navigatordo)[subcomp]at(0.8666, 3.5)odo; (navigatornav)[subcomp]a
    loc[senscomp]at(4.6, 4.8); (omni - ball)[sensstcmp]at(4.6, 3.2); (omni -
    field)[senscomp]at(4.6, 1.6); (stereo -
    obs)[senscomp]at(4.6, 0); (worldmodel)[touchcomp, minimumwidth =
    6.0cm, rotate =
90]at(10.4, 0)worldmodel; (skiller)[speccomp]at(11.6, 4.4); (agent)[speccomp]at(11.6, 1.9); (image)[resource, mi
    1.6cm, rotate = 90]at(3.8, 0)Image; (network)[resource, minimumwidth =
    2.6cm, ]at(11.6, 0)Network;
    (kicker.north west) node [below right] kicker;
    (fvbase.north west) node [below right] fvbase; (stereo-obs.north west) node
    [below right] stereo-obs; (omni-field.north west) node [below right] omni-field;
    (navigator.north west) node [below right] navigator; (skiller.north west) node
    [below right] skiller; (agent.north west) node [below right] agent;
    (omni-loc.north west) node [below right] omni-loc; (omni-ball.north west) node
    [below right] omni-ball;
    [conn,-\i] (fvbase.east) - (image.north); [conn,-\i] (image.south) - +(0.4,0)
coordinate (A) --- ((omni - loc.west) + (0, -0.2)); [conncirc] (A) circle (0.05);
    [conn,-\i] (A --- omni-ball.west) - (omni-ball.west); [conn,-\i] (A ---
    omni-field.west) - (omni-field.west); [conn,-\i] (A) --- (stereo-obs.west);
    [ccs] (kicker.east) --- +(0.4,0.8) - +(1.2,0.8) coordinate (A); [cce] (A) ---
    ((skiller.north) + (0.4, 0)); (A) node [below right,inner ysep=0.2em] kicking;
    [ccs] (navigatordo.south) - +(1.9, -0.4)coordinate(A); [cce](A) - - +
    (0.6, 0) - ((omni-loc.west) +
    (0,0.2)); (A)node[below, innerysep = 0.3em]odometry;
    [ccs] (navigatornav.east) - | + (0.8, 2.8) - - +
    (1.6, 2.8)coordinate(A); [cce](A) - |((skiller.north) -
    (0.4,0)); (A)node[belowright, innerysep = 0.2em]navigation;
    [ccs]
    (navigatoract.north) - ((navigatoract.north - |navigatordo.north) + (0, 0.2))
    coordinate (A); [cce] (A) --- (navigatornav.north);
    [ccs] (stereo-obs.east) - +(0.8,0) coordinate (A); [cce] (A) - (stereo-obs.east
    --- worldmodel.north); (A) node [below,inner ysep=0.4em] obstacles;
    [ccs] (omni-field.east) - +(0.8,0) coordinate (A); [cce] (A) - (omni-field.east
    --- worldmodel.north); (A) node
    (robotpose1)[below, innerysep = 0.4em]obstacles;
    [ccs] (omni-loc.east) - +(0.8,0) coordinate (A); [cce] (A) - (omni-loc.east ---
    worldmodel.north); (A) node [below,inner ysep=0.4em] robot pose;
    [ccs] (omni-ball.east) - +(0.8,0) coordinate (A); [cce] (A) - (omni-ball.east ---
    worldmodel.north); (A) node [below,inner ysep=0.5em] ball pos;

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