

# Project III -Deliberating and Acting

Group 1

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# Hardware

- CMU cam
- 2 slot encoders
- 2 reflectance sensors
- 1 range sensor
- 1 servo
- 2 drive motors

# Software

- Subsumption architecture

- collect known boxes

if box is present

  approach target

  grab nearby box

  find nearest goal

  approach target

  drop box in goal

else

  realign

# Contd

- collect unknown objects

realign

go to nearest corner then start sweeping

if found a box

    move to target

    grab nearby box

    target nearest goal

    approach target

    drop box in goal

else

    realign