Robot Library Reference

behControl Library:

behControl.init(funcList): Takes a list of functions as input and executes functions using a hierarchy. If there is no active behavior, red LEDs slowly blink. The first function in the list has the highest priority, while the last function has the lowest priority.

behControl.robotStart(): Red LEDs circle until the red button is pushed, then program execution can begin. Velocity, leds, and neighbors are all initialized. Input: None, Output: None.

behControl.robotEnd(): All LEDs are turned off and the motors are stopped. Input: None, Output: None.

behControl.runBehFor(time): Updates system for the input amount of time and delays changing it. Input: time - amount of time in microseconds to runBehFor the behavior controller, Output: None.

behControl.setTv(tv): Function used to set the translational velocity. Input: tv - translational velocity, Output: None.

behControl.setRv(rv): Function used to set the rotational velocity. Input: rv - rotational velocity, Output: None.

behControl.setTvRv(tv, rv): Function used to set both the tv and rv part of velocity. Input: tv - rotational velocity, rv - translational velocity, Output: None.