Robot Library Reference

behControl Library:

`behControl.init(funcList)`: Takes a list of functions as input and executes functions using a heirarchy. 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.