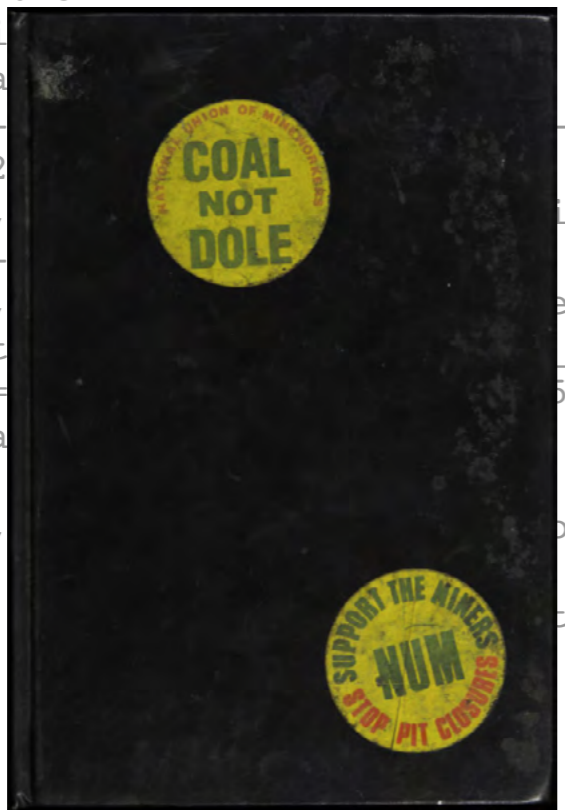


```

float max_room_xcm = 1000 //694
float max_room_ycm = 1100 // 1005
/*HH2!2*///-----trajectory-----//new
int section_list[32]
/*HH2!2*///-----neural networks ----- // new
float theta, theta_next, r
int steps_nb_max = 16
int k, current_grid
int section_size[40]
/float section_boost= 150
/old section based
/float section_boost= 50
/ new node based for trajectory
float section_boost= 90 // test using 1. Should be 90
/ new node based for field drawing
/float section_boost= 0.3
/ very new node + si
float forced_next_sta
/*HH2!2*///-----
float section_speed[2]
int current_section,
/*HH2!2*///-----
int keyboard, color,
float time_since_last
int min_range_check =
int echo[max_sonar_a
float found_flag, xs,
float sonar_dir[8+1],
sonar_y[8+1]
int front_obstacle,
sonar_dir[1]=-PI/2
sonar_dir[2]=3*PI/4
sonar_dir[3]=-PI
sonar_dir[4]=PI/2
sonar_dir[5]=PI/2
sonar_dir[6]=PI/2
sonar_dir[7]=0
sonar_dir[8]=PI/4
sonar_x[1] = 0
sonar_y[1]= -10
sonar_x[2] = -26
sonar_y[2]= 7
sonar_x[3] = -26
sonar_y[3]= 37
sonar_x[4] = -26
sonar_y[4]= 51

```



```

// new
float right_speed
= 0
alarm = 0
500
sonar_range[8+1], sonar_x[8+1],
acle

```



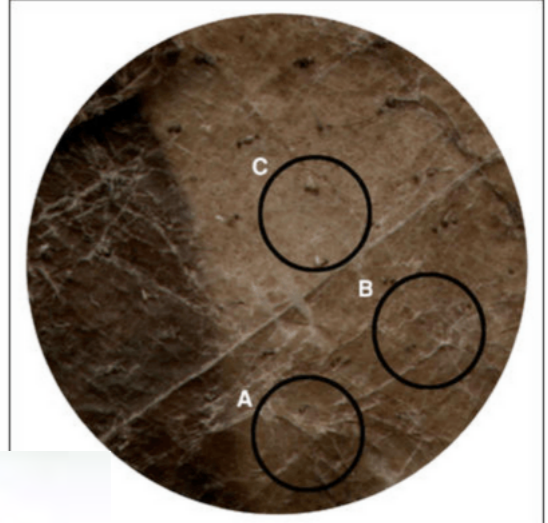
come trust -----



```

// version june - july 2012 Wellcome exhibition
// wheelchair project 97
// modif of wshow2.ctx by adding correct
// trajectories encoding from wshow3.ctx
//from wshow6.ctx
/*SH1!1
/*HS1!1
int re
int be
int i
int ol
int st
int me
int se
// a s
float f
int left_speed = 1, right_
float right_speed_desired =
float left_speed_desired =
/*HH2!2*///-----positi
float PI = 4*arctan(1)
float phi2, angle1, angle2,
float x_wc=0, y_wc=0, phi_wc
float x_wc_shift=0, y_wc_sh
float old_x_wc=0, old_y_wc=
float d_x_wc_dt, d_y_wc_dt,
float x_wc_predict, y_wc_pr
float previous_phi_wc, prev
float x_shaft, y_shaft, phi
float w_x_shaft, w_y_shaft,
float d_x_shaft_dt, d_y_shaft_dt, d_phi_shaft_dt
float old_x_shaft, old_y_shaft, old_phi_shaft
float phi_gyro, w0_gyro, w_phi_gyro, d_phi_gyro_dt
float phi_camera, w_phi_camera, d_phi_camera_dt
float phi_cam1, phi_cam2
float x_sonar, y_sonar, phi_sonar
float w0_sonar, w_x_sonar, w_y_sonar, w_phi_sonar
float d_x_sonar_dt, d_y_sonar_dt, d_phi_sonar_dt
float last_time_shaft
/*HH2
float
/*HH
-----

```



```

cluding room dimensions
ables-----
110, gyro_data = 105, gyro_reset = 12
44, sending_byte = 55, command_send
s = 99, motor_command = 107
limit = 500

```

