

# Route Calculation

- Corridor detection
- Location in corridor
- Map
- Route calculator
- Motor controller

# Drive Node

- Middle Drive
- Parallel drive left/right
- Turn left/right

# Arrow detection

MessageRoute [int distanceToDrive, int toDoMotor]

MessageDrive [int toDoMotor]

messageCloseToGap [bool closeToGapLeft, bool closeToGapRight]

MessageArrow [bool turnLeft]

# Motor Controller

Publish to motor