nanomax.rbt Page 1 of 1

nanomax.rbt

Routine drives out to vicinity of jiggly table, makes a 180 degree turn to sweep off molecules, and position rear light sensor for line following. Robot then follows line until it backs into nanotube trip lever. Robot stops and begins an almost 360 turn to face the ATP motor, hopefully trips the nanotube lever while turning, and then drops ATP molecules. Robot then requires manual retrieval.

