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<ahss-config>

<!-- ***** -->
<!-- Experiment-specific parameters -->
<!-- ***** -->

<framework>

  <!-- How long a clock tick lasts (in milliseconds) -->
  <clocktick>100</clocktick>

  <!-- Maximum simulation clock ticks -->
  <maxclock>300</maxclock>

  <random_seed>1234</random_seed>

</framework>

<!-- ***** -->
<!-- Controller-specific parameters -->
<!-- ***** -->

<controllers>

  <my_simple_footbot_controller id="myfootbot" library="object_code_for_my_controller">

    <sensors>
      <footbot_proximity>
        <implementation>generic_footbot_proximity</implementation>
      </footbot_proximity>

      <camera_vision>
        <implementation>generic_camera_vision</implementation>
        <camera_resolution>1024x1024</camera_resolution>
      </camera_vision>

      <wifi_radio>
        <implementation>generic_wifi_radio</implementation>
      </wifi_radio>
    </sensors>

    <actuators>
      <footbot_wheels>
        <implementation>footbot_wheels</implementation>
      </footbot_wheels>

      <wifi_radio>
        <implementation>generic_probabilistic_wifi_radio</implementation>
        <radio_range>60</radio_range>
        <interference_probability>0.1</interference_probability>
        <loss_probability>0.05</loss_probability>
      </wifi_radio>
    </actuators>

    <parameters>      <!-- user parameters with their default values -->
      <initial_behavior>random_moving</initial_behavior>
      <avg_speed>3</avg_speed>
      <avg_radius>2</avg_radius>
    </parameters>

  </my_simple_footbot_controller>

</controllers>

<!-- ***** -->
<!-- Arena configuration (dimensions, robots, other entities) -->
<!-- ***** -->

<arena size="5, 5, 2" optimization="2D" >

  <footbot id="fb1">
    <position>0, 0, 0</position>
    <orientation>0, 0, 30</orientation>
    <controller>myfootbot</controller>
    <parameters>
      <initial_behavior>do_not_move</initial_behavior>
    </parameters>
  </footbot>

  <footbot id="fb2">
    <position>2, 2, 0</position>
    <orientation>0, 0, -120</orientation>
    <controller>frc</controller>
    <parameters>
      <avg_speed>10</avg_speed>
      <avg_radius>5</avg_radius>
    </parameters>
  </footbot>

</arena>

<!-- ***** -->
<!-- Describe the physics engines that dictate movement and collision -->
<!-- ***** -->

<engines>

  <2d_engine id="ground">
    <subclock>1</subclock>
    <perpendicular_axis>z</perpendicular_axis>
    <distance>0</distance>
  </2d_engine>

</engines>

<!-- ***** -->
<!-- Mapping between physics engines and entities -->
<!-- ***** -->

<arena_physics>

  <engine id="ground">
    <entity id="fb1" />
    <entity id="fb2" />
  </engine>

</arena_physics>

<!-- ***** -->
<!-- Visualisation-specific parameters -->
<!-- ***** -->

<visualisations>

  <text_render id="text_world">
    <file>experiment_output.txt</file>
    <precision>2</precision>
  </text_render>

  <opengl_render id="mainwindow">
    <window_size>768, 768</window_size>
    <camera_view_XYZ_0>3, 3, 5</camera_view_XYZ_0>
    <camera_view_HPR_0>0, -90, 0</camera_view_HPR_0>
    <window_title>Test Experiment</window_title>
    <use_textures>true</use_textures>
  </opengl_render>

</visualisations>

</ahss-config>

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