task main()

{

wait10Msec(50);

// all these loops have the robot go forward while a condition is true then stops when false

while(SensorValue(touch)==0) // you are not hitting something

{

motor(right)=30;

motor(left)=30

}

motor(right)=0;

motor(left)=0

wait10Msec(50);

//----------------------------------------------------------------------------------------------

while(SensorValue(touch)!=0) // NOT EQUAL or ==1. you are hitting something - pushing it

{

motor(right)=30;

motor(left)=30

}

motor(right)=0;

motor(left)=0

wait10Msec(50);

//----------------------------------------------------------------------------------------------

while(SensorValue(sonar)>20) // nothing is in front of you

{

motor(right)=30;

motor(left)=30

}

motor(right)=0;

motor(left)=0

wait10Msec(50);

//----------------------------------------------------------------------------------------------

while(SensorValue(sonar)<20) // something is in front of you

{

motor(right)=30;

motor(left)=30

}

motor(right)=0;

motor(left)=0

wait10Msec(50)

//----------------------------------------------------------------------------------------------

while(SensorValue(light)!=2) //you don't see blue - stops when it sees blue

{

motor(right)=30;

motor(left)=30

}

motor(right)=0;

motor(left)=0

wait10Msec(50);

//----------------------------------------------------------------------------------------------

while(SensorValue(light)==6) // as long as you are on the white paper

{

motor(right)=30;

motor(left)=30

}

motor(right)=0;

motor(left)=0

wait10Msec(50);

//----------------------------------------------------------------------------------------------

nMotorEncoder[right]=0; // resets the encoder to 0

while(nMotorEncoder[right]<473) // as long as the wheels have not turned 473 clicks

{

motor[right]=40;

motor[left]=40;

}

motor[right]=0;

motor[left]=0;

wait10Msec(50);

//----------------------------------------------------------------------------------------------

clearTimer(T1); // clears the timer

while(time10[T1] < 300) // will repeat for 3 seconds

{

motor(right)=30;

motor(left)=30

}

motor(right)=0;

motor(left)=0

wait10Msec(50);

//----------------------------------------------------------------------------------------------

/\* if you put statements inside the while statements braces{ } the robot will do two things

as it is going forward it will check the if as see if it is true

ex.

while(SensorValue(light)!=2) //you don't see blue - stops when it sees blue

{

motor(right)=30;

motor(left)=30

if(SensorValue(sonar)<20) // if something is in your way turn right

{

rturn();

}

}

motor(right)=0;

motor(left)=0

wait10Msec(50);

}

\*/