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);

 }

 \*/