Diagram, schematic

Description automatically generated

Using E-Puck robot

Webots software

C programming language

Software logic:

* Detect an obstacle by distance sensors [ps6, ps7, ps0, ps1]
* If obstacle near to [ps6,ps7] {left obstacle}the robot will turn 90 degree right by turning the left wheel and stop the right wheel
* For loop and counter are used to turn 90 degrees