```
if (decyzja == 'J' || decyzja == 'j')
	{
		bool shouldBreak = false;
		int rotation = 1;
		do
		{

		distance = NXT::Sensor::GetSonarValue(&comm, IN_1);
		int scan_counter = 0;
		while (distance >= 75)
		{
		if (kbhit() == true)
		{
			shouldBreak = true;
			decyzja = getch();
			break;
		}
		if (rotation == 1)
		{
			NXT::Motor::SetReverse(&comm, OUT_B, y);
			NXT::Motor::SetForward(&comm, OUT_C, y);
		}
		else
		{
			NXT::Motor::SetForward(&comm, OUT_B, y);
			NXT::Motor::SetReverse(&comm, OUT_C, y);
		}
		distance = NXT::Sensor::GetSonarValue(&comm, IN_1);
		Wait(50);
		scan_counter++;
		if (scan_counter == XXX)
		{
			rotation *= -1;
			scan_counter = 0;
		}

		}
		NXT::Motor::SetForward(&comm, OUT_B, x);
		NXT::Motor::SetForward(&comm, OUT_C, x);
		if (kbhit() == true)
		{
		shouldBreak = true;
		decyzja = getch();
		break;
		}
		color = NXT::Sensor::GetValue(&comm, IN_2);
		while (color >= xxx)
		{
```

```
        if (kbhit() == true)
        {
                shouldBreak = true;
                decyzja = getch();
                break;
        }

        color = NXT::Sensor::GetValue(&comm, IN_2);
        Wait(50);
        }
        NXT::Motor::SetForward(&comm, OUT_B, 0);
        NXT::Motor::SetForward(&comm, OUT_C, 0);
        NXT::Motor::Stop(&comm, OUT_B, 0);
        NXT::Motor::Stop(&comm, OUT_C, 0);
        rotation *= -1;
        } while (shouldBreak == false);

}
```