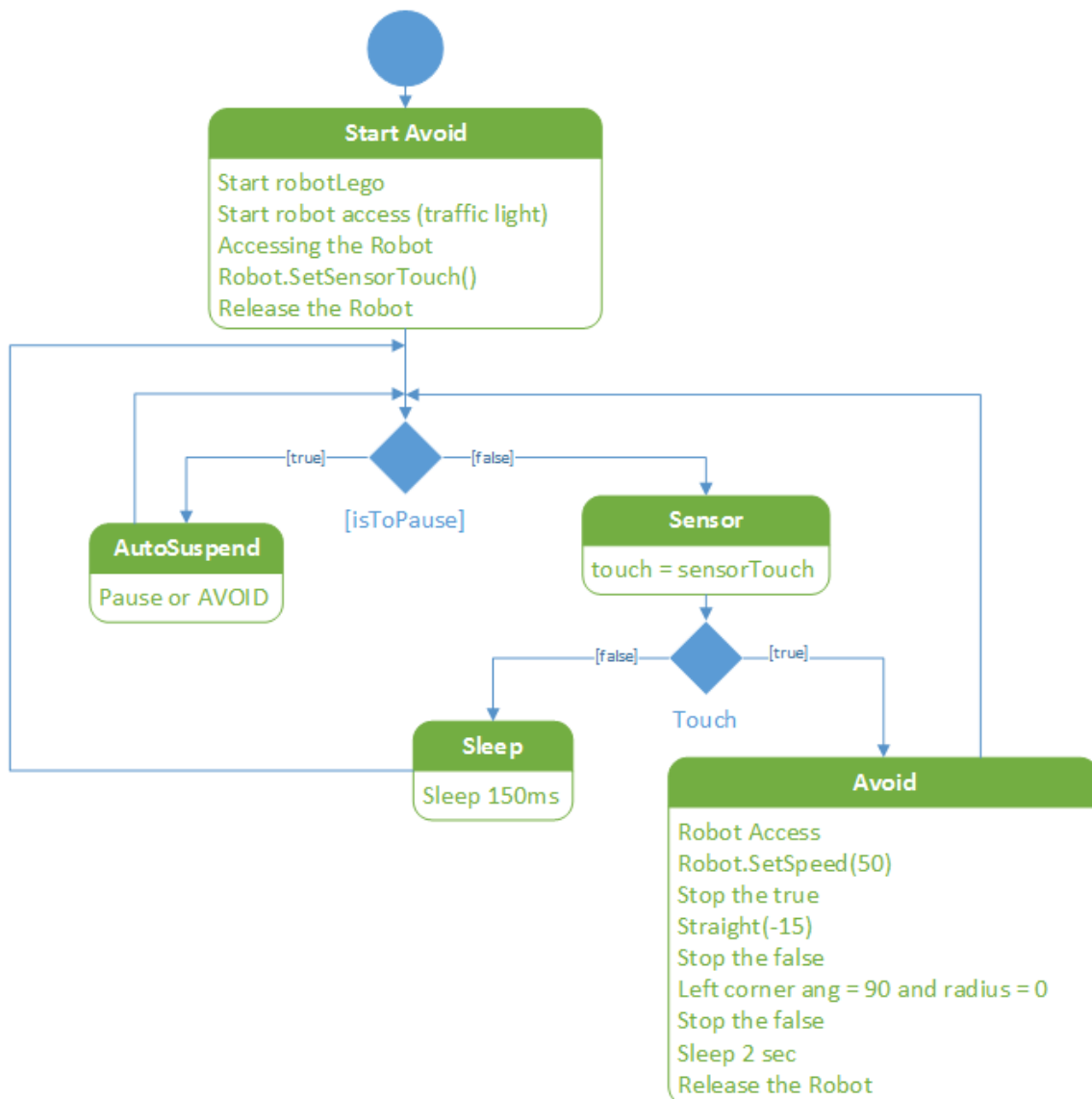


Avoid



When the Robot hits an obstacle, it performs the Avoid behavior.

Start by setting the Robot's touch sensor and then check if this behavior was not put on pause. If it wasn't, it can then read the sensor, which returns the value of "1" in case of collision and "0" otherwise. If it returns "1" then it accesses the Robot (always in exclusion), it makes a small straight back (15 centimetres) and a curve to the left with a radius of 0 centimetres and with an angle of 90 degrees. To let the Robot finish executing the instructions, the behavior "sleeps" 2 seconds (enough time to finish the instructions) and finally it can go back to the beginning where it is checked if this behavior is put in pause. If you return "0" (represented in the figure by false), the behavior "sleeps" for a defined instant (150 milliseconds) and then repeat everything again.