**Practical no. 4**

import ch.aplu.robotsim.\*;

public class LineFollower

{

LineFollower()

{

LegoRobot robot=new LegoRobot();

Gear gear=new Gear();

LightSensor ls=new LightSensor(SensorPort.S3);

robot.addPart(gear);

gear.setSpeed(20);

robot.addPart(ls);

while(true)

{

int v=ls.getValue();

if(v < 100)//black

gear.forward();

if(v > 300 && v < 750) //blue

gear.leftArc(0.05);

if(v> 800) //yellow

gear.rightArc(0.05);

}

}

public static void main(String args[])

{

new LineFollower();

}

static

{

RobotContext.setStartPosition(50,490);

RobotContext.setStartDirection(-90);

RobotContext.useBackground("sprites/road.gif");

}

}

**Output:**

