**Practical No. 6**

import ch.aplu.robotsim.\*;

public class PathFinder

{

public PathFinder()

{

NxtRobot robot=new NxtRobot();

Gear gear=new Gear();

LightSensor ls1=new LightSensor(SensorPort.S1);

LightSensor ls2=new LightSensor(SensorPort.S2);

robot.addPart(gear);

robot.addPart(ls1);

robot.addPart(ls2);

gear.forward();

while(true)

{

int rightValue=ls1.getValue();

int leftValue=ls2.getValue();

int d=rightValue - leftValue;

if(d>100)

gear.rightArc(0.1);

if(d < -100)

gear.leftArc(0.1);

if(d > -100 && d < 100 && rightValue > 500)

gear.forward();

}

}

public static void main(String args[])

{

new PathFinder();

}

static

{

NxtContext.setStartPosition(250,490);

NxtContext.setStartDirection(-90);

NxtContext.useBackground("sprites/path.gif");

}

}

**Output:**

