**Practical no. 7**

import ch.aplu.robotsim.\*;

import ch.aplu.util.\*;

public class resistobst

{

public resistobst()

{

LegoRobot robot = new LegoRobot();

Gear g = new Gear();

TouchSensor ts1 = new TouchSensor(SensorPort.S1);

TouchSensor ts2 = new TouchSensor(SensorPort.S2);

robot.addPart(g);

robot.addPart(ts1);

robot.addPart(ts2);

g.forward();

while(!QuitPane.quit())

{

Boolean t1 = ts1.isPressed();

Boolean t2 = ts2.isPressed();

if(t1 && t2)

{

g.backward(500);

g.left(400);

g.forward();

}

else

{

if(t1)

{

g.backward(500);

g.left(400);

g.forward();

}

else

{

if(t2)

{

g.backward(500);

g.right(100);

g.forward();

}

}

}

Tools.delay(20);

}

robot.exit();

}

public static void main(String [] args)

{

new resistobst();

}

static

{

RobotContext.setLocation(10,10);

RobotContext.setStartDirection(5);

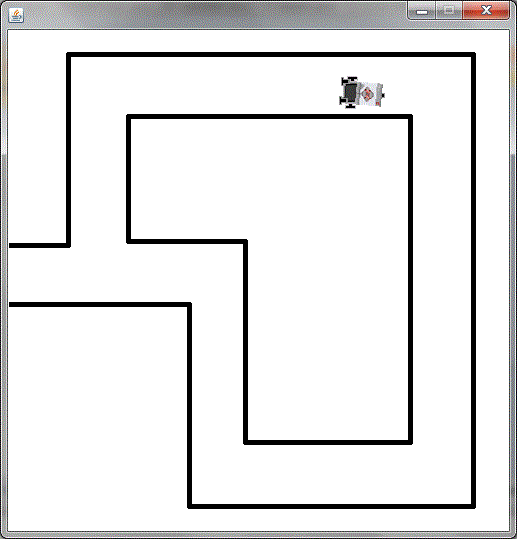
RobotContext.setStartPosition(100,240);

RobotContext.useObstacle(RobotContext.channel);

}

}

**Output:**

****