**Search and Rescue Library**

This library contains methods that will be useful for the Lego Mindstorm Search and Rescue activity. Examples include methods that can be used to follow a black line, make turns at intersections, turn around, detect obstacles, and detect a person that needs rescuing.

**StartLineFollow() –** Begins the line following code. This needs to be called once, at the beginning of the program.

**StopLineFollow() –** Stops the line following code. The motors of the robot will be turned off.

**WaitUntilTurn() –** Before any other instructions can be carried out, a turn must be made. Any code made after this statement will not be executed until the robot makes a turn.

**WaitUntilPress(int sensorNumber) –** Before any other instructions can be carried out, the robot must bump into something. Any code made after this statement will not be executed until the robot touches something. To use this method, you must pass it the number of the touch sensor attached to your robot.

**TurnAround() –** Rotates the robot 180 degrees. This is useful for when there is an obstacle in the way, or after you’ve found a person and you don’t want to run them over!

**TurnRight() –** At the next intersection the robot will take the path going to the right.

**TurnLeft() –** At the next intersection the robot will take the path going to the left.

**GoStraight() –** At the next intersection the robot will take the path that continues going straight.