Quadrant 4

dist\_right = (IR\_left + IR\_right)/2 //distance to hug the right wall at

While true

IR\_left = Get IR scanner measurement left

IR\_right = Get IR scanner measurement right

if(\*at the gate\* = true){ //not sure if there will be a red card in front of gate??

For (i=0; i < 6; i++)

Dist\_gate = IR\_frount //check distance from gate

If (dist\_gate > max) //find distance when gate open

Max = dist\_gate

sleep(1,0)

While (! IR\_frount < max)

\*at the gate\* = false;

Break // get out of while loop so it can go forward

}

If (IR\_right > wall\_dist\_right){ //keeps robot at correct distance

Turn\_right

}

Else { // if bot is too close to the left wall

turn\_left

}