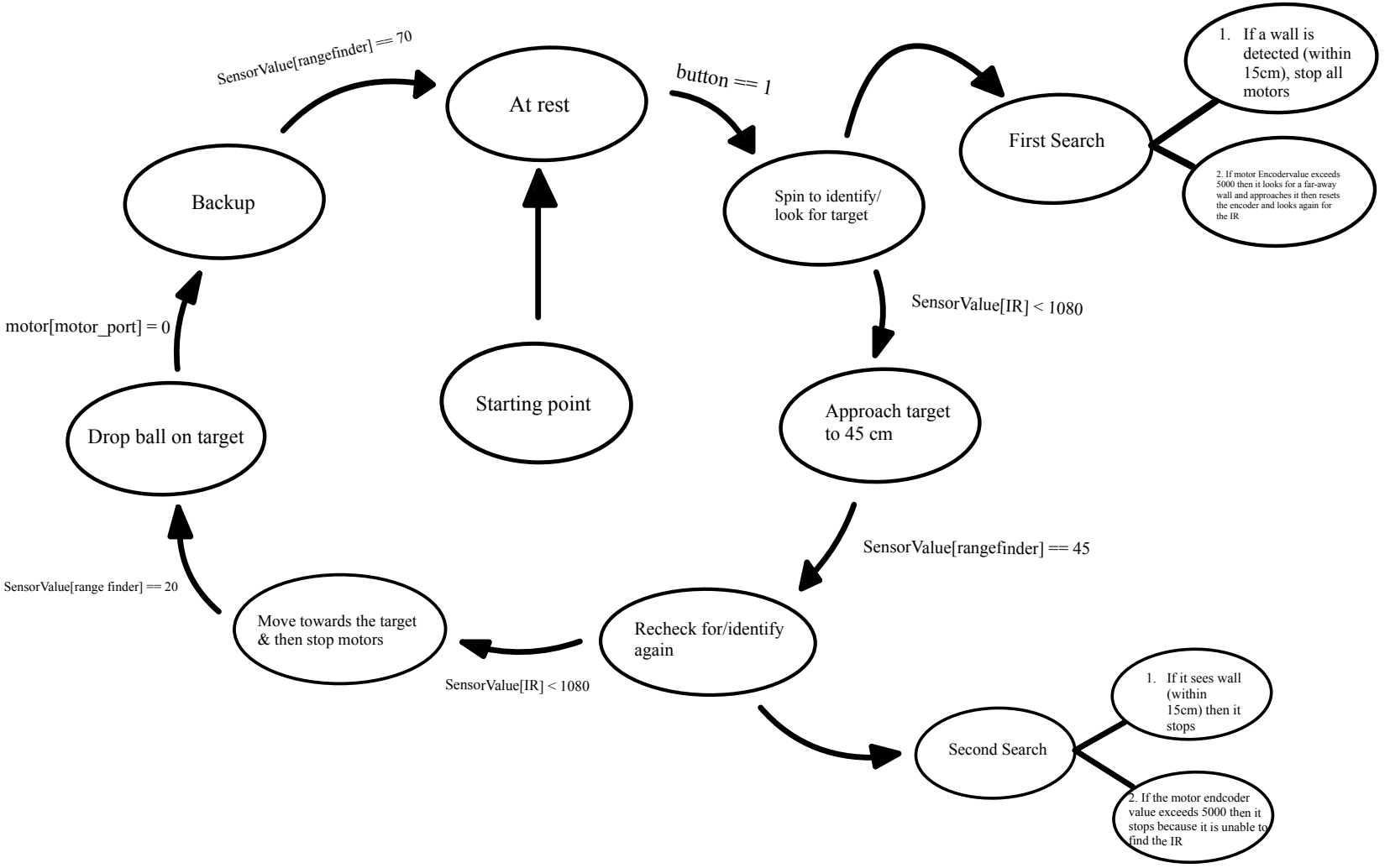
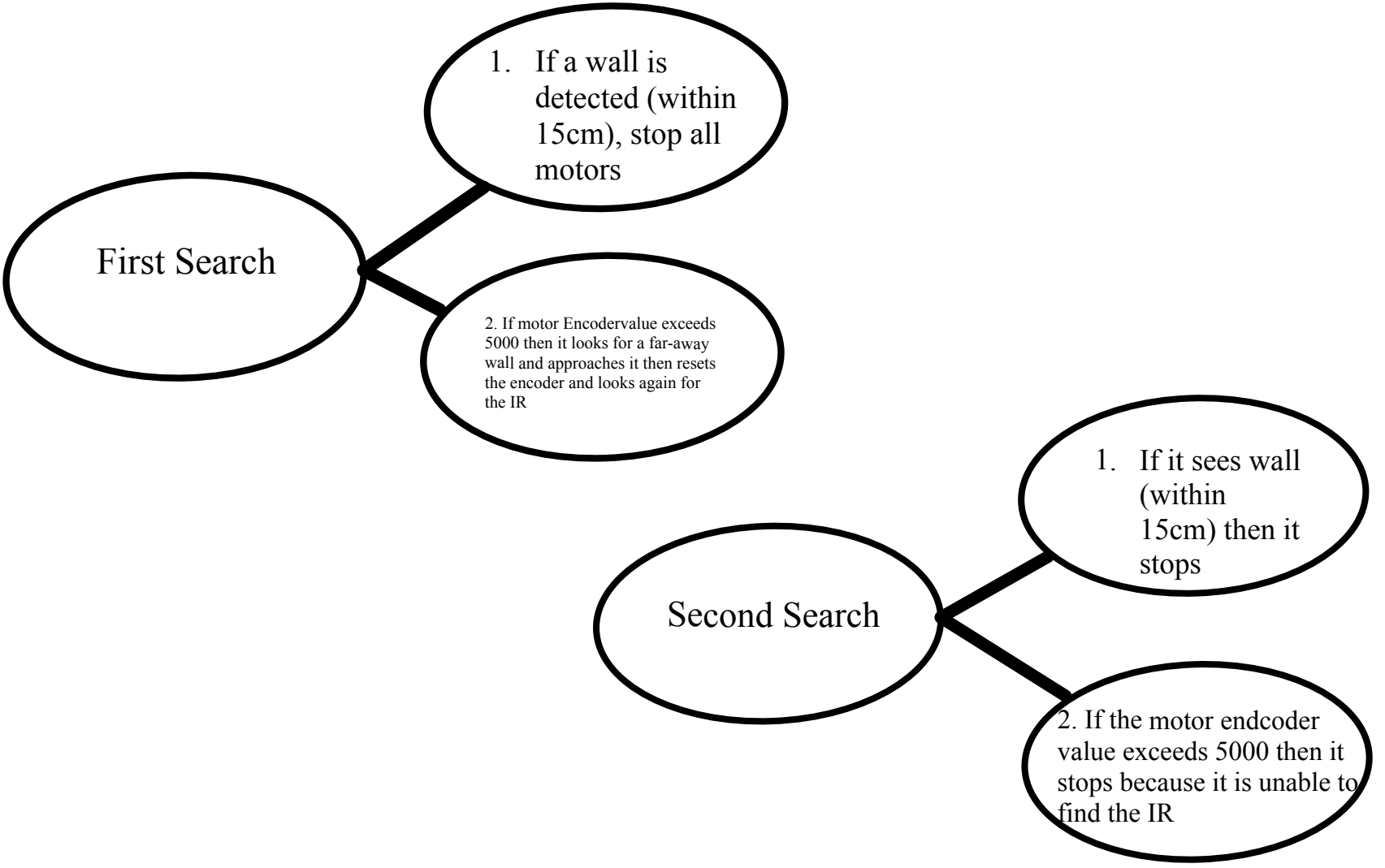

At rest
button == 1
Spin to identify/ look for target
First Search
1. If a wall is detected (within 15cm), stop all motors
2. If motor Encodervalue exceeds 5000 then it looks for a far-away wall and approaches it then resets the encoder and looks again for the IR
SensorValue[IR] < 1080
Approach target to 45 cm
SensorValue[rangefinder] == 45
Recheck for/identify again
Second Search
1. If it sees wall (within 15cm) then it stops
2. If the motor endcoder value exceeds 5000 then it stops because it is unable to find the IR
SensorValue[IR] < 1080
Move towards the target & then stop motors
SensorValue[range finder] == 20
Drop ball on target
motor[motor_port] = 0
Backup
SensorValue[rangefinder] == 70
Starting point


First Search
1. If a wall is detected (within 15cm), stop all motors
2. If motor Encodervalue exceeds 5000 then it looks for a far-away wall and approaches it then resets the encoder and looks again for the IR
Second Search
1. If it sees wall (within 15cm) then it stops
2. If the motor endcoder value exceeds 5000 then it stops because it is unable to find the IR