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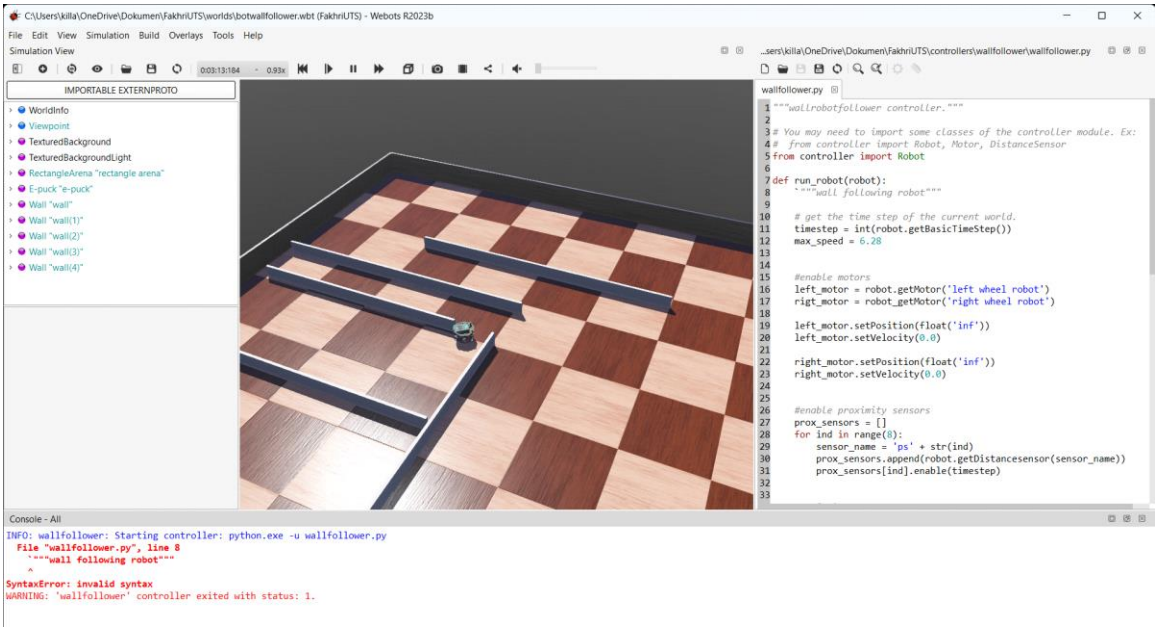
Saya membuat robot dengan prototype e-puck model yang cocok untuk menjadi wall follower.



source code:

"""wallrobotfollower controller."""

You may need to import some classes of the controller module. Ex:

from controller import Robot, Motor, DistanceSensor

from controller import Robot

def run_robot(robot):

`"""wall following robot"""

get the time step of the current world.

timestep = int(robot.getBasicTimeStep())

max_speed = 6.28

```
#enable motors
left_motor = robot.getMotor('left wheel robot')
rigt_motor = robot_getMotor('right wheel robot')

left_motor.setPosition(float('inf'))
left_motor.setVelocity(0.0)

right_motor.setPosition(float('inf'))
right_motor.setVelocity(0.0)



#enable proximity sensors
prox_sensors = []
for ind in range(8):
    sensor_name = 'ps' + str(ind)
    prox_sensors.append(robot.getDistancesensor(sensor_name))
    prox_sensors[ind].enable(timestep)



# Main loop:
# - perform simulation steps until Webots is stopping the controller
while robot.step(timestep) != -1:
    # Read the sensors:
    for ind in range(8):
        print("ind: {}, val: {}".format(ind, prox_sensors[ind].getValue()))

    # Process sensor data here.
```

```
    left_wall = prox_sensors[5] .getValue() > 80
    front_wall = prox_sensors[7] .getValue() > 80

    left_speed = max_speed
    right_speed = max_speed

    if front_wall:
        print("Turn right in place")
        left_speed = max_speed
        right_speed = max_speed

     else:
         if left_wall:
             print("Drive Forward")
             left_speed = max_speed
             right_speed = max_speed

         else:
             print("Turn Left")
             left_speed = max_speed/4
             right_speed = max_speed

    # Enter here functions to send actuator commands, like:
    #   motor.setPosition(10.0)
    left_motor.setVelocity(max_speed)
    right_motor.setVelocity(max_speed)


# Enter here exit cleanup code.
```

```
if __name__ == "__main__":

    # create the Robot instance.
     my_robot = Robot()
     run_robot(my_robot)
```