```
task main()
{
  SensorType[S1] = sensorEV3_Touch;
  SensorType[S2] = sensorEV3_Ultrasonic;
  SensorType[S3] = sensorEV3_Color;
  SensorType[S4] = sensorEV3_Gyro;

  bool isUp = false, isRight = false;
  const int DRIVE_LIM = 60 * 360 / (2 * PI * 2.75);

  displayString(4, "JB");

  while((!getButtonPress(buttonUp)) && (!getButtonPress(buttonDown)))
  {}

  if(getButtonPress(buttonUp))
    isUp = true;

  while((getButtonPress(buttonUp)) && (getButtonPress(buttonDown)))
  {}

  eraseDisplay();

  if(isUp)
  {
    motor[motorA] = motor[motorD] = -25;
  }
  else
  {
    motor[motorA] = motor[motorD] = 25;
  }

  nMotorEncoder[motorA] = 0;

  while(abs(nMotorEncoder[motorA]) < DRIVE_LIM)
  {}

  motor[motorA] = motor[motorD] = 0;

  while(!getButtonPress(buttonRight) && !getButtonPress(buttonLeft))
  {}

  if(getButtonPress(buttonRight))
    isRight = true;

  while(getButtonPress(buttonRight) && getButtonPress(buttonLeft))
  {}

  if(isRight)
  {
    motor[motorA] = 25;
    motor[motorD] = -25;
  }
  else
  {
    motor[motorA] = -25;
    motor[motorD] = 25;
  }
  wait1Msec(1250);

  motor[motorA] = motor[motorD] = 0;

  wait1Msec(500);

  if(isRight)
  {
    motor[motorA] = -25;
    motor[motorD] = 25;
  }
  else
  {
    motor[motorA] = 25;
    motor[motorD] = -25;
  }

  wait1Msec(1250);
}
```