File: C:\Users\angelika\Desktop\Coding Practice\RobotC\Test.c

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

  float origDist = 0;
  const float FINAL_DIST = 20 + 15;

  displayString(4, "JB");

  nMotorEncoder[motorA] = 0;

  while(!getButtonPress(ENTER_BUTTON))
  {}

  while(getButtonPress(ENTER_BUTTON))
  {}

  eraseDisplay();

  motor[motorA] = motor[motorD] = 25;

  while(SensorValue[S1] == 0)
  {}

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

  origDist = nMotorEncoder[motorA];

  wait1Msec(500);

  motor[motorA] = motor[motorD] = -25;

  while(SensorValue[S2] < FINAL_DIST)
  {}

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

  wait1Msec(1000);

  motor[motorA] = motor[motorD] = -25;

  while(nMotorEncoder[motorA] > origDist*(-2))
  {}

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

  displayString(7, "%f", origDist);

  wait1Msec(10000);

}
```