from WePort import \*

from WeUltrasonicSensor import \*

from WeDCMotor import \*

import time

from WeServo import \*

ultrasonic\_A = WeUltrasonicSensor(PORT\_A)

dc\_1 = WeDCMotor(1)

ultrasonic\_B = WeUltrasonicSensor(PORT\_B)

ultrasonic\_C = WeUltrasonicSensor(PORT\_C)

servo\_1 = WeServo(1, 0)

while True:

if ultrasonic\_A.distanceCM() < 15:

dc\_1.run(0)

ultrasonic\_A.rgbShow(3, 247, 3, 3)

time.sleep(0.1)

while not ultrasonic\_A.distanceCM() > 50:

dc\_1.run(-100)

else:

if ultrasonic\_B.distanceCM() < ultrasonic\_C.distanceCM():

servo\_1.write\_angle(105)

dc\_1.run(150)

ultrasonic\_B.rgbShow(3, 247, 3, 3)

if ultrasonic\_C.distanceCM() < ultrasonic\_B.distanceCM():

servo\_1.write\_angle(70)

dc\_1.run(150)

ultrasonic\_C.rgbShow(3, 247, 3, 3)

if ultrasonic\_C.distanceCM() == ultrasonic\_B.distanceCM():

servo\_1.write\_angle(85)

dc\_1.run(180)

ultrasonic\_C.rgbShow(3, 247, 3, 3)