```cpp
1  #include "uss.h"
2  #include "../vars/constants.h"
3
4  class Sensors
5  {
6      private:
7      uss Front = uss(constants::pins::uss::Front_Sens,
         constants::pins::uss::Trigger);
8      uss Back  = uss(constants::pins::uss::Back_Sens,
         constants::pins::uss::Trigger);
9      uss Left  = uss(constants::pins::uss::Left_Sens,
         constants::pins::uss::Trigger);
10     uss Right = uss(constants::pins::uss::Right_Sens,
         constants::pins::uss::Trigger);
11
12     public:
13     bool CanGoFront()
14     {
15         Serial.println(Front.MeasureDistance());
16         return true;
17         return Front.MeasureDistance() >
            constants::uss::FrontBack_Min_Distance;
18     }
19     bool CanGoBack()
20     {
21         return Back.MeasureDistance() >
            constants::uss::FrontBack_Min_Distance;
22     }
23     bool CanGoLeft()
24     {
25         return Left.MeasureDistance() >
            constants::uss::Side_Min_Distance;
26     }
27     bool CanGoRight()
28     {
29         return Right.MeasureDistance() >
            constants::uss::Side_Min_Distance;
30     }
31  };
```