

```

#pragma config(Sensor, S4,      light,
sensorLightActive)
#pragma config(Motor,  motorA,          left,
tmotorNXT, PIDControl, encoder)
#pragma config(Motor,  motorC,          right,
tmotorNXT, PIDControl, encoder)
/*!!Code automatically generated by 'ROBOTC' configuration
wizard          !!*/
void lefty()
{
    if(SensorValue[light]<50)
    {
        motor[left]=-50;
        motor[right]=-50;
        wait1Msec(500);
        nMotorEncoder[left]=0;
        nMotorEncoder[right]=0;
        while(nMotorEncoder[right]<920)
        {
            motor[left]=0;
            motor[right]=50;
        }
    }
}

void righty()
{
    if(SensorValue[light]<50)
    {
        motor[left]=-50;
        motor[right]=-50;
        wait1Msec(500);
        nMotorEncoder[left]=0;
        nMotorEncoder[right]=0;
        while(nMotorEncoder[left]<920)
        {
            motor[left]=50;
            motor[right]=0;
        }
    }
}

task main()
{
    int count=0;
    while(1)
    {

```

```
if(SensorValue[light]<50)
{
    if(count %2 == 1)
    {
        lefty();
        count++;
    }
    else
    {
        righty();
        count++;
    }
}
else
{
    motor[left]=50;
    motor[right]=50;
}
}}
```