```
#pragma config(Sensor, S1,      light,
sensorLightActive)
#pragma config(Sensor, S2,      sen,            sensorSONAR)
#pragma config(Motor,  motorA,              left,
tmotorNXT, PIDControl, driveLeft, encoder)
#pragma config(Motor,  motorC,              right,
tmotorNXT, PIDControl, driveRight, encoder)
//*!!Code automatically generated by 'ROBOTC' configuration
wizard               !!*//

void stoprobot()
{
    motor[left]=0;
    motor[right]=0;
    wait1Msec(1000);
}
void clearencoder()
{
    nMotorEncoder[left]=0;
    nMotorEncoder[right]=0;
}
void leftturn()
{
    while(nMotorEncoder[right]<460)
        {
        motor[left]=0;
            motor[right]=50;
        }
}
void rightturn()
{
    while(nMotorEncoder[left]<460)
        {
        motor[left]=50;
            motor[right]=0;
        }
}
void move()
{
        while (SensorValue(sen)>15) //No Obstacle
        {
        motor[left]=50;
        motor[right]=50;
        }
}
```

```
task main()
{
    while(1)
    {
        move();
        while (SensorValue(sen)<=15)
        {
            stoprobot();
            clearencoder();
            leftturn();
        }

    }
}
```