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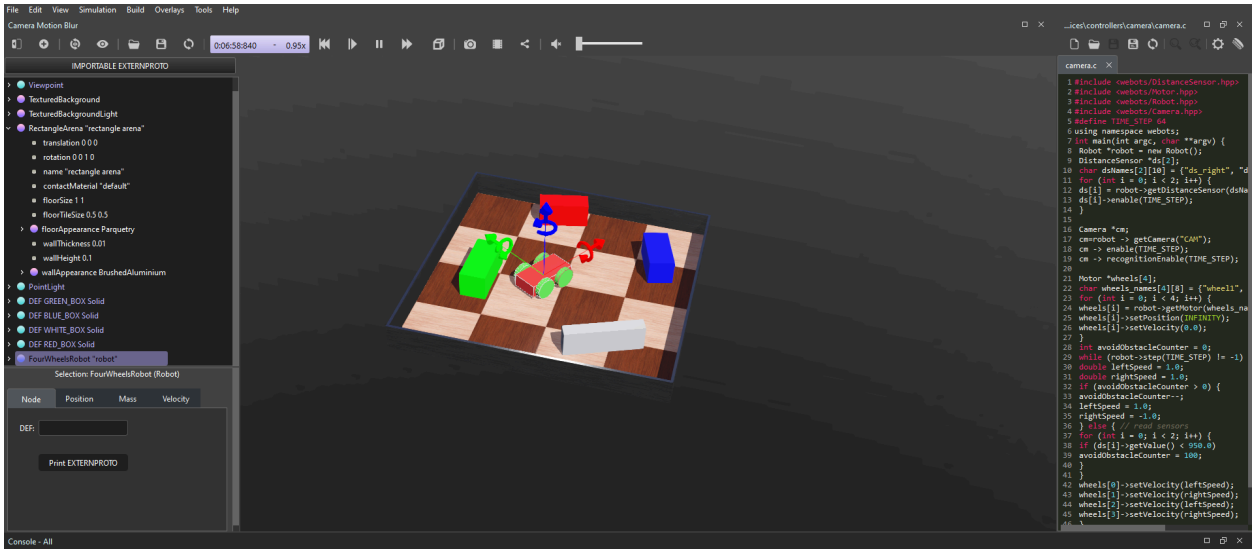

source code

```
#include <webots/DistanceSensor.hpp>
#include <webots/Motor.hpp>
#include <webots/Robot.hpp>
#include <webots/Camera.hpp>
#define TIME_STEP 64
using namespace webots;
int main(int argc, char **argv) {
 Robot *robot = new Robot();
 DistanceSensor *ds[2];
 char dsNames[2][10] = {"ds_right", "ds_left"};
 for (int i = 0; i < 2; i++) {
 ds[i] = robot->getDistanceSensor(dsNames[i]);
 ds[i]->enable(TIME_STEP);
 }

 Camera *cm;
 cm=robot -> getCamera("CAM");
 cm -> enable(TIME_STEP);
 cm -> recognitionEnable(TIME_STEP);

 Motor *wheels[4];
 char wheels_names[4][8] = {"wheel1", "wheel2", "wheel3", "wheel4"};
 for (int i = 0; i < 4; i++) {
 wheels[i] = robot->getMotor(wheels_names[i]);
 wheels[i]->setPosition(INFINITY);
 wheels[i]->setVelocity(0.0);
 }
```

```
int avoidObstacleCounter = 0;
while (robot->step(TIME_STEP) != -1) {
double leftSpeed = 1.0;
double rightSpeed = 1.0;
if (avoidObstacleCounter > 0) {
avoidObstacleCounter--;
leftSpeed = 1.0;
rightSpeed = -1.0;
} else { // read sensors
for (int i = 0; i < 2; i++) {
if (ds[i]->getValue() < 950.0)
avoidObstacleCounter = 100;
}
}
wheels[0]->setVelocity(leftSpeed);
wheels[1]->setVelocity(rightSpeed);
wheels[2]->setVelocity(leftSpeed);
wheels[3]->setVelocity(rightSpeed);
}
delete robot;
return 0;
} // EXIT_SUCCESS
```