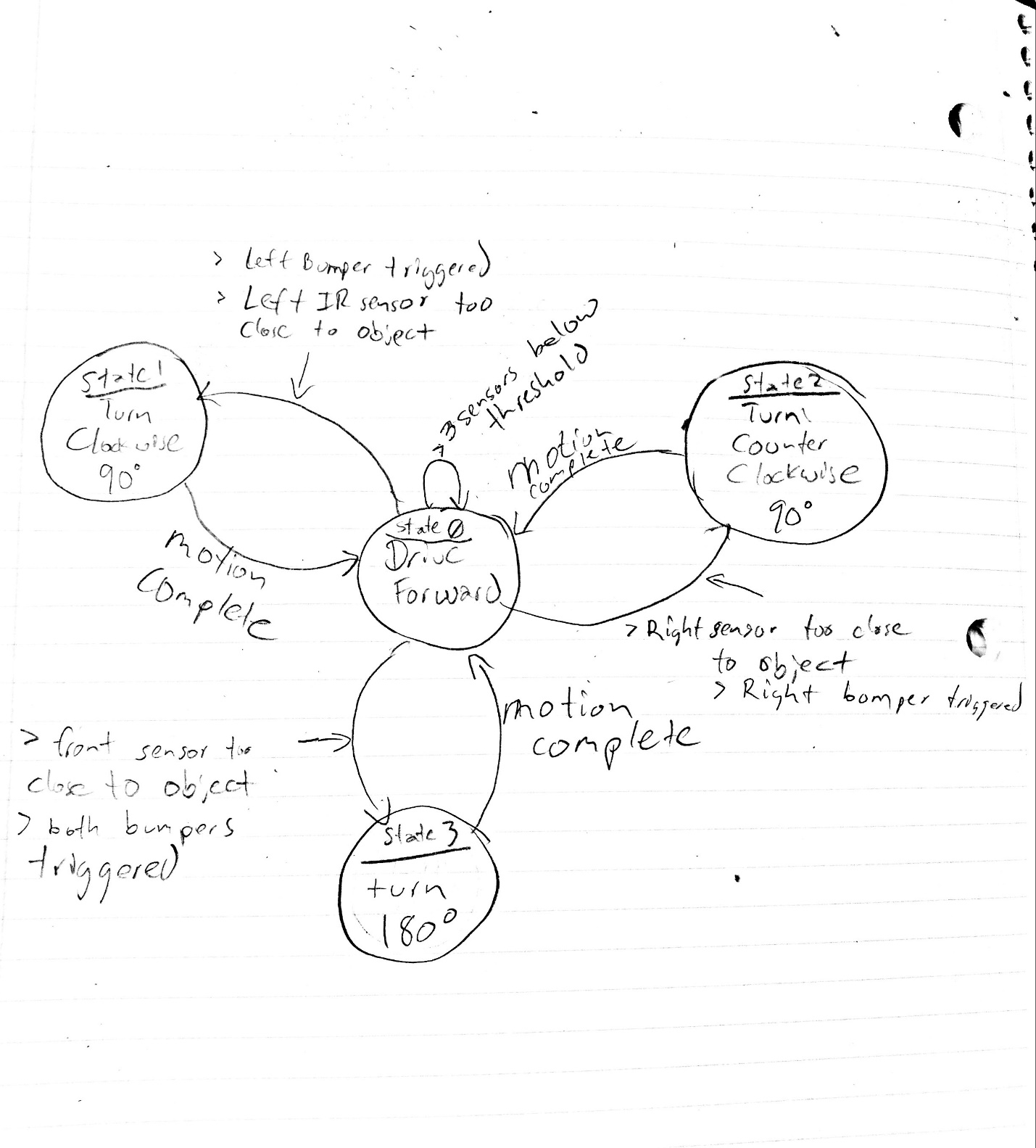
Steve Guerrero

ECPE 155

Prelab 5



Pseudocode (kinda)

“Assuming” front sensor has an overall lower reading than left or right sensors

if((IR\_Front<=1000) && (IR\_RIGHT<=2100) && (IR\_LEFT<=1950)){

//Keep driving forward until an object is detected

all\_FWD(); // both wheels forward

}else if((IR\_FRONT>1000) && (IR\_RIGHT<=2100) && (IR\_LEFT<=1950)){

//Front sensor detects an obstacle, stop bust a U and drive in opposite direction

CW\_90(); // rotate clockwise 90 degrees

CW\_90(); // rotate clockwise 90 degrees

all\_FWD(); // both wheels forward

}else if((IR\_FRONT>1000) && (IR\_RIGHT>2100) && (IR\_LEFT<=1950)){

//Front and Right IR sensor detect obstacle, rotate CCW

CCW\_90(); // rotate counter clockwise 90 degrees

all\_FWD(); // both wheels forward

}else if((IR\_FRONT>1000) && (IR\_RIGHT<=2100) && (IR\_LEFT>1950)){

//Front and Left IR sensor detect obstacle, rotate CW

CW\_90(); // rotate clockwise 90 degrees

all\_FWD(); // both wheels forward

}else if((IR\_FRONT<=1000) && (IR\_RIGHT>3000) && (IR\_LEFT<=1950)){

//Robot is driving too close to an obstacle on the Right, rotate CCW

CCW\_90(); // rotate counter clockwise 90 degrees

all\_FWD(); // both wheels forward

}else if((IR\_FRONT<=1000) && (IR\_RIGHT<=2100) && (IR\_LEFT>3000)){

//Robot is driving too close to an obstacle on the Left, rotate CW

CW\_90(); // rotate clockwise 90 degrees

all\_FWD(); // both wheels forward

}else{

//Keep driving forward

all\_FWD(); // both wheels forward

}