```
PROTO receiver_bot [

        field SFString controller "receiver"

]

{

        DEF RECEIVER_BOT Robot {

         translation 0.15 0 0

         rotation 0 1 0 1

         children [

          DEF MAIN_BODY Transform {

           translation 0 0.0415 0

           children [

              Shape {

               appearance PBRAppearance {

                baseColor 0.0820075 0.364731 0.8

                roughness 1

                metalness 0

               }

               geometry DEF BODY Cylinder {

                height 0.08

                radius 0.045

               }

              }

           ]

          }

          HingeJoint {

           jointParameters HingeJointParameters {

              axis -1 0 0

              anchor 0 0.025 0

           }

           device [

              RotationalMotor {
```

```
      name "left wheel motor"

      consumptionFactor 70

      maxVelocity 100

    }

    PositionSensor {

      name "left wheel sensor"

    }

  ]

  endPoint Solid {

      translation -0.045 0.025 0

      rotation 1 0 0 4.98467

      children [

        DEF WHEEL Transform {

          rotation 0 0 1 1.57

          children [

            Shape {

              appearance PBRAppearance {

                baseColor 1 0 0

                roughness 1

                metalness 0

              }

              geometry Cylinder {

                height 0.01

                radius 0.025

              }

            }

          ]

        }

      ]

      name "left wheel"

      boundingObject USE WHEEL
```

```
        physics DEF PHYSICS_WHEEL Physics {

         density -1

         mass 0.05

        }

  }

}

HingeJoint {

  jointParameters HingeJointParameters {

      axis -1 0 0

      anchor 0 0.025 0

  }

  device [

      RotationalMotor {

       name "right wheel motor"

       consumptionFactor 70

       maxVelocity 100

      }

      PositionSensor {

       name "right wheel sensor"

      }

  ]

  endPoint Solid {

      translation 0.045 0.025 0

      rotation 1 0 0 4.58735

      children [

       USE WHEEL

      ]

      name "right wheel"

      boundingObject USE WHEEL

      physics USE PHYSICS_WHEEL

  }
```

```
    }
DEF LEFT_EYE DistanceSensor {
 translation -0.02 0.063 -0.042
 rotation 0 1 0 2.07
 children [
      DEF SENSOR Transform {
       rotation 0 0 1 1.57
       children [
        Shape {
         appearance PBRAppearance {
          baseColor 0.975691 0.981481 0.0252992
          roughness 1
          metalness 0
         }
         geometry Cylinder {
          height 0.004
          radius 0.008
         }
        }
       ]
      }
 ]
 name "ds0"
 lookupTable [
      0 1024 0
      0.05 1024 0
      0.15 0 0
 ]
 numberOfRays 2
 aperture 1
}
```

```
DEF RIGHT_EYE DistanceSensor {
  translation 0.02 0.063 -0.042
  rotation 0 1 0 1.07
  children [
      USE SENSOR
  ]
  name "ds1"
  lookupTable [
      0 1024 0
      0.05 1024 0
      0.15 0 0
  ]
  numberOfRays 2
  aperture 1
}
DEF SMILE Transform {
  translation 0 0.025 -0.036
  rotation 0.7745972408364944 0.44721228048294853 0.4472139204829502 1.8234794
  children [
      Shape {
        appearance PBRAppearance {
          baseColor 0.721569 0.290196 0.290196
          roughness 1
          metalness 0
        }
        geometry Cylinder {
          height 0.018
          radius 0.009
          subdivision 3
        }
      }
```

```
      ]
    }
    DEF RECEIVER Receiver {
      translation 0 0.06 0
      rotation 0 1 0 3.1415
      type "infra-red"
      channel 1
    }
  ]
  name "MyBot receiver"
  boundingObject DEF MYBOT_BOUNDING Transform {
    translation 0 0.0415 0
    children [
      USE BODY
    ]
  }
  physics DEF MYBOT_PHYSICS Physics {
    density -1
    mass 0.5
  }
  controller IS controller
  }
}
```