```
#pragma config(Sensor, in1,    lineFollower,   sensorLineFollower)
#pragma config(Sensor, in2,    potentiometer,  sensorPotentiometer)
#pragma config(Sensor, in3,    lightSensor,    sensorReflection)
#pragma config(Sensor, dgtl1,  limitSwitch,    sensorTouch)
#pragma config(Sensor, dgtl2,  bumpSwitch,     sensorTouch)
#pragma config(Sensor, dgtl3,  quad,           sensorQuadEncoder)
#pragma config(Sensor, dgtl5,  sonar,          sensorSONAR_inch)
#pragma config(Sensor, dgtl12, green,          sensorLEDtoVCC)
#pragma config(Motor,  port2,          rightMotor,    tmotorVex393_HBridge, ope
#pragma config(Motor,  port1,          flashlight,    tmotorVexFlashlight, open
#pragma config(Motor,  port9,          servoMotor,    tmotorServoStandard, open
#pragma config(Motor,  port10,         leftMotor,     tmotorVex393_HBridge, ope
/*
Project Title: Motor and Servo practice program
Team Members: POE Curriculum Team
Date: Friday 10 Feb 2017
Task Description: Too long to type out
Pseudocode:
Repeat indefinitely:
Wait for bump
Motors spin half speed
led on
when light sensor above 700, spin servo
stop motors
wait 2 sec
motors spin reverse 2 sec half speed
wait 3 sec
when light sensor less than 400 set servo 120
motors off

*/
void allMotors (int speed){ //Little function I wrote a while ago to change the
  motor[leftMotor]=speed;
  motor[rightMotor]=speed;
}

task main()
{
  while (true) { //Keep going, and so we have a chance to press the button
    if (SensorValue[bumpSwitch]==1){ //Wait for button
      allMotors(63); //Half speed
      turnLEDOn(green); //Self-explanatory
      while (true){ //Again, keep going so we have a chance to trigger the light
        if (SensorValue[lightSensor]>700){
          motor[servoMotor]=63; //Then set the servo to a value of 63 (half turn
          allMotors(0);
          wait1Msec(2000);
          allMotors(-63); //Go backwards half speed
          wait1Msec(3000);
          while (true){ //Give a chance for light sensor to be uncovered
            if (SensorValue[lightSensor]<400){
              motor[servoMotor]=120;
              allMotors(0);
              break; //Get out of this while loop and continue
            }
          }
```

```
        break; //Get out of this while loop to restart this program.
      }
    }

  }
 }
}
```