# # You may need to import some classes of the controller module. Ex:

from controller import Robot, Motor, DistanceSensor, CameraRecognitionObject

from controller import Robot, Camera

# sensor = robot.getDevice("my\_distance\_sensor")

def run\_robot(robot):

    time\_step = 32

    max\_speed = 6.28

    # Motors

    left\_motor = robot.getDevice('left wheel motor')

    left\_motor.setPosition(float('inf'))

    left\_motor.setVelocity(0.0)

    right\_motor = robot.getDevice('right wheel motor')

    right\_motor.setPosition(float('inf'))

    right\_motor.setVelocity(0.0)

    camera = robot.getDevice("camera\_top")

    camera.enable(time\_step)

    camera.recognitionEnable(time\_step)

    camera.enableRecognitionSegmentation()

    while robot.step(time\_step) != -1:

        left\_speed = -max\_speed

        right\_speed = max\_speed

        left\_motor.setVelocity(left\_speed)

        right\_motor.setVelocity(right\_speed)

        if len(camera.getRecognitionObjects()) > 0:

            object\_detected = True

            print('Object Detected')

            firstObject = camera.getRecognitionObjects()[0]

            position\_on\_image = firstObject.get\_position\_on\_image()

            print(position\_on\_image)

            x = position\_on\_image[0]

            y = position\_on\_image[1]

            # if 20<= x <=30:

            if x/y >= 0.5:

                print('Moving Towards the object')

                left\_speed = max\_speed

                right\_speed = max\_speed

                left\_motor.setVelocity(left\_speed)

                right\_motor.setVelocity(right\_speed)

        else:

            object\_detected = False

            print('Object Not Detected')

        # firstObject = camera.getRecognitionObjects()[0]

        # #num\_objects = camera.getRecognitionNumberOfObjects()

        # # id = firstObject.get\_id()

        # #position = firstObject.get\_position()

        # # position\_on\_image = firstObject.get\_position\_on\_image()

        # # orientation = firstObject.get\_orientation()

        # print(firstObject)

if \_\_name\_\_ == '\_\_main\_\_':

    my\_robot = Robot()

    run\_robot(my\_robot)

Morning Gratitude:

1. I am Grateful for……
2. What would make today Great……
3. Todays Affirmation

Evening:

1. Amazing things happened today
2. How could I have made it better