--------------------------------------------------

**TR Program in Pseudocode (Group 16)**

--------------------------------------------------

/\*

\* Making use of subsumption principles,

\* purpose is to drive towards light source

\* while avoiding obstacles.

\*/

main {

touchSensorPressed => avoidObstacle

lightDetected, facingLight => driveForward

lightDetected, !facingLight => turnTowardsLight

true => scanForLight //default case when no light detected

}

/\*

\* Drives backwards for 1 second, turns a direction depending

\* on which touch sensor was pressed then drives forwards for

\* 1 second

\*/

avoidObstacle {

leftTouchSensorPressed => driveBackward, turnRight, driveForward

rightTouchSensorPressed => driveBackward, turnLeft, driveForward

}

/\*

\* Turns towards light depending on robots current orientation

\*/

turnTowardsLight {

lightOnLeft => turnLeft

lightOnRight => turnRight

}

/\*

\* Turn until robot facing light

\*/

scanForLight {

!facingLight => turnRight

true => nil

}