

## 6.8 Line follower

### 6.8.1 Tasks:

1. Write the program to control the robot follow the line ( actually above the edge between black and white area ). Some programming hints you can find in prog. 1 :

#### Program 1: Line Follower.

```
1  #include "RobotMovingFunctions.h"
2  const int LIGHT_SENSOR_PIN = A0;
3  const int SURFACE_BRIGHTNESS_REFERENCE = 400;
4
5  void setup()
6  {
7      setIOpins();
8      pinMode(LIGHT_SENSOR_PIN , INPUT);
9  }
10
11 void loop()
12 {
13     int light_sensor_value = analogRead(LIGHT_SENSOR_PIN );
14     if ( light_sensor_value < treshold_value )
15     {
16         // do this if robot is over the black line
17
18     }
19     else
20     {
21         // do this if robot is over white area
22
23     }
24 }
```

### 6.8.2 Questions:

1. What is the program function to get the `light_sensor_value`?
2. Determine the movements of the robot if the robot is over the black area and if the robot is over the white area.

### 6.8.3 Summary:

#### 6.8.3.1 <++> <++>

#### **6.8.4 Issues:**

##### **6.8.4.1 <++> <++>**