* Robot starts by moving forward at full-speed (regardless of orientation, don’t use color sensor)
  + If it hits white periphery, back up and turn 180° --since arena is a ring, robot will face center no matter what → ramming speed!
* If robot hits white line (in the back color-sensor), move forward)

OR

* Keep spinning until distance is <50 cm (20 inches)
* If distance <50 cm, ramming speed!
* Else, spinning
* If robot hits white line (front color sensor), move backward and turn 180° --since arena is a ring, robot will face center no matter what → then move forward for 2 seconds (so it can enter ultrasonic sensor range) → reenter loop
* If robot hits white line (back color sensor), move forward and enter ultrasonic loop