\*red disk

[turn left

walk forward until the next right step is not a solid barrier

turn right

walk until the next step is a solid barrier

turn right

take disk

turn right

walk until the next step is a solid barrier

stop

turn left

walk until the next left step is not a solid barrier

stop

turn right

step forward

turn right

set disk

turn right

step forward]

\*green disk

[turn right

walk forward until the next left step is not a solid barrier

turn left

walk until the next left step is a pile of disks

turn left

take disk

turn left

walk until the next right step is not a solid barrier

step forward

turn left

set disk

turn right

step forward]

tell robot to

do \*red disk twice

do \*green disk

do \*red disk

do \*green disk

do \*red disk

do \*green disk

do \*red disk twice