

LAB 2 – Wall Following

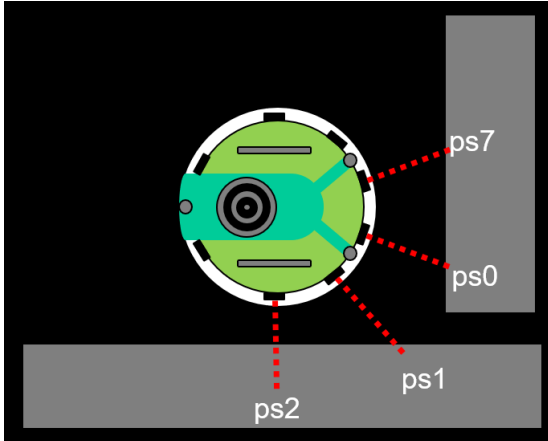
- (1)** Download the **Lab2_WallFollowing.zip** file and unzip it. Load up the **MessyRoom** world. The goal of this lab is to make the robot perform right-handed wall-following from its start location up to the mirror. Your robot should NOT run into anything.



- (2)** The **Lab2Controller** code has been started for you. Follow the state machine that has been given in the notes. You will only be making use of the following **4** proximity sensors ->

You should build up your code slowly, handling one scenario at a time. Perhaps follow the order of the slides as the state machine is built up in the notes.

You will need to tweak the amounts of curving and pivoting to get your code to work just right. Set the maximum speed of the robot to **5** and your robot should be going roughly at full speed most of the time.



Submit your **Lab2Controller.java** code once you are done. Make sure that your name and student number is in the first comment line.