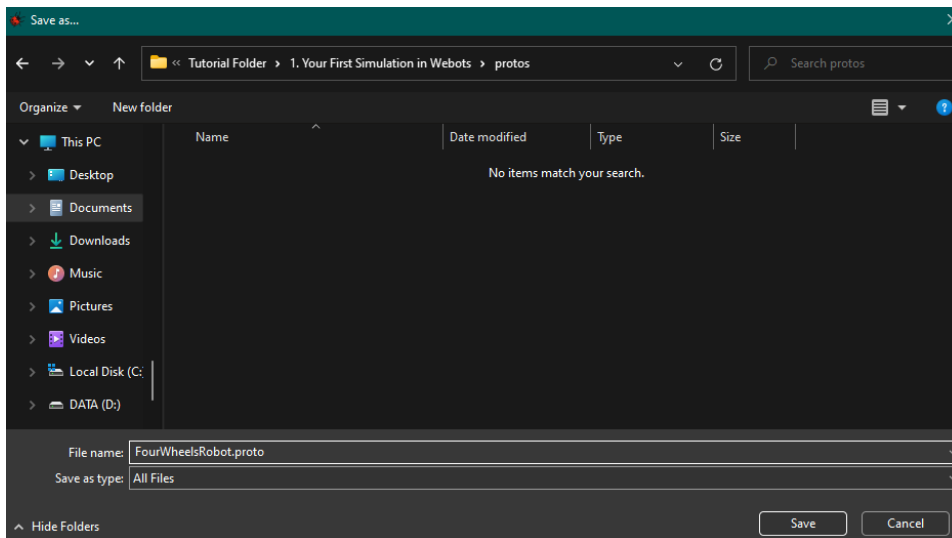


Hands-on 1



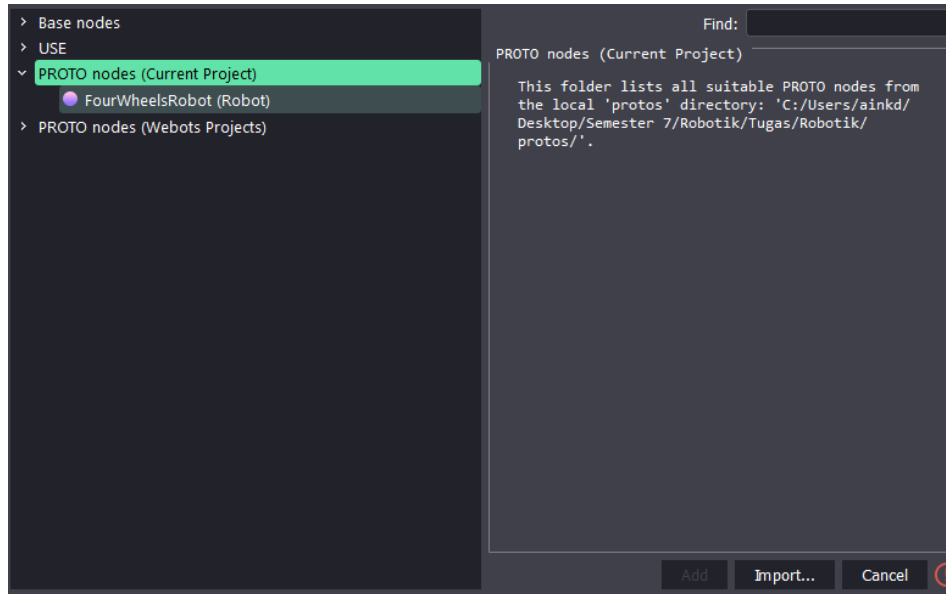
Hands-on 2

```

FourWheelsRobot.proto
1 #VRML_SIM R2023a utf8
2 PROTO FourWheelsRobot [
3
4 ]
5 {
6   Robot {
7     translation 0.1615533173615318 -0.09824954769125145 0.0398621001
8     rotation 4.091617753830915e-06 2.6371308084952304e-07 -0.9999999
9     children [
10      DistanceSensor {
11        translation 0.098 0.020077 0
12        rotation 0 0 1 -1.27
13        children [
14          DEF SENSOR Shape {
15            appearance PBRAppearance {
16              baseColor 0 0.666667 1
17              roughness 1
18              metalness 0
19            }
20            geometry Box {
21              size 0.01 0.01 0.01
22            }
23          }
24        ]
25        name "ds_left"
26        boundingObject USE SENSOR
27        physics Physics {
28        }
29      }
30      DistanceSensor {
31        translation 0.098 -0.019923 0
32        rotation 0 0 1 -1.87
33        children [
34          DEF SENSOR Shape {
35            appearance PBRAppearance {
36              baseColor 0 0.666667 1
37              roughness 1
38              metalness 0
39            }
40            geometry Box {
41              size 0.01 0.01 0.01
42            }
43          }

```

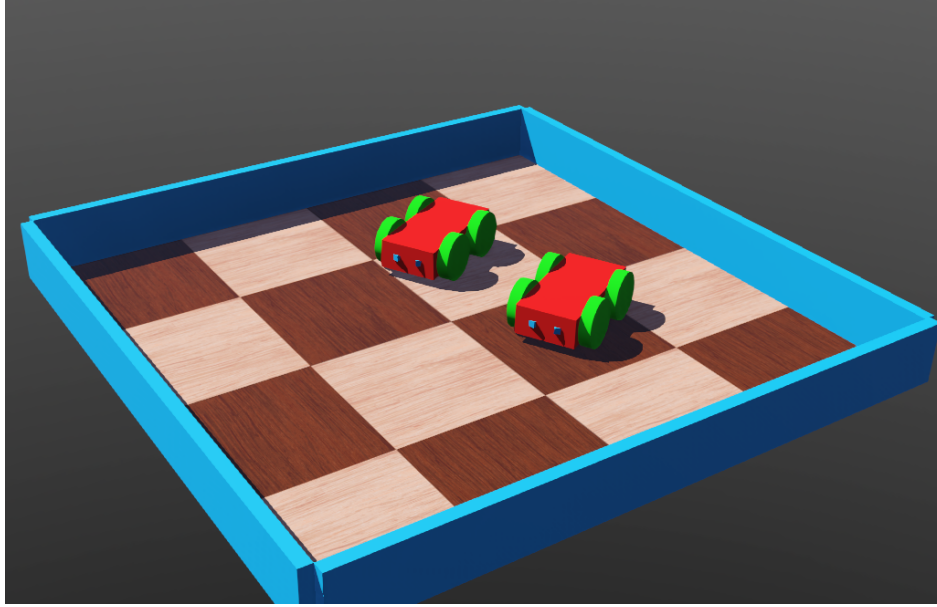
Hands-on 3




Hands-on 4

```

FourWheelsRobot.proto* X
1  #VRML_SIM R2023a utf8
2  PROTO FourWheelsRobot [
3    field SFVec3f    translation  0 0 0
4    field SFRotation rotation    0 0 1 0
5    field SFFloat    bodyMass    1
6  ]
7  {
8    Robot {
9      translation IS translation
10     rotation IS rotation
11     children [
12
13
14     boundingObject USE BODY_GEOMETRY
15     physics Physics {
16       mass IS bodyMass
17     }
18     controller "four_wheeled_collision_avoidance"
19   }
20 }
    
```



>  FourWheelsRobot "robot"