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Arduino run first:
Setup
Version 1
Configure obstacle detection: left sensor pin# D2 , right sensor pin# D0
Configure drive robot: left motor pin# D3 , right motor pin# D6
Stop robot

Arduino loop forever:
set txtObsSen to get obstacle
if txtObsSen = N
do
else if
do
Drive robot Rotate Left for 2 seconds
else if
do
else if txtObsSen = F
do
```

```
Drive robot Backward Left for 2 seconds
```

```
txtObsSen = L
```

```
Drive robot Rotate Right for 2 seconds
```

```
Drive robot Forward
```

```
txtObsSen = R
```