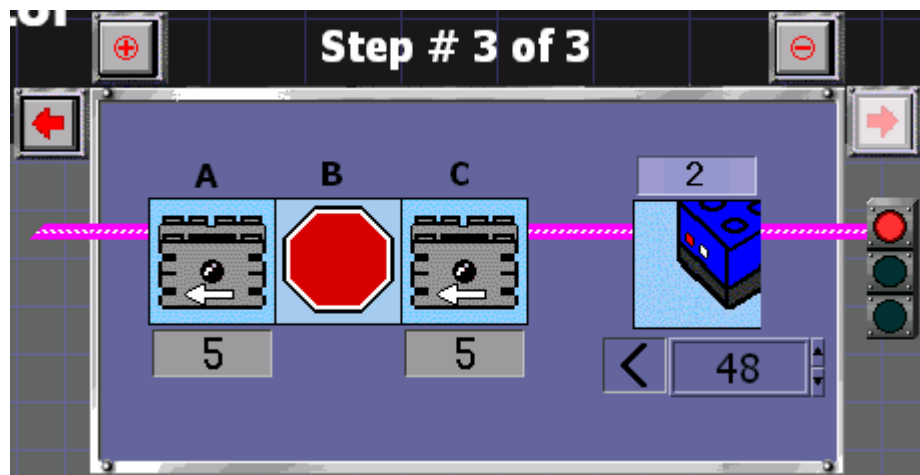
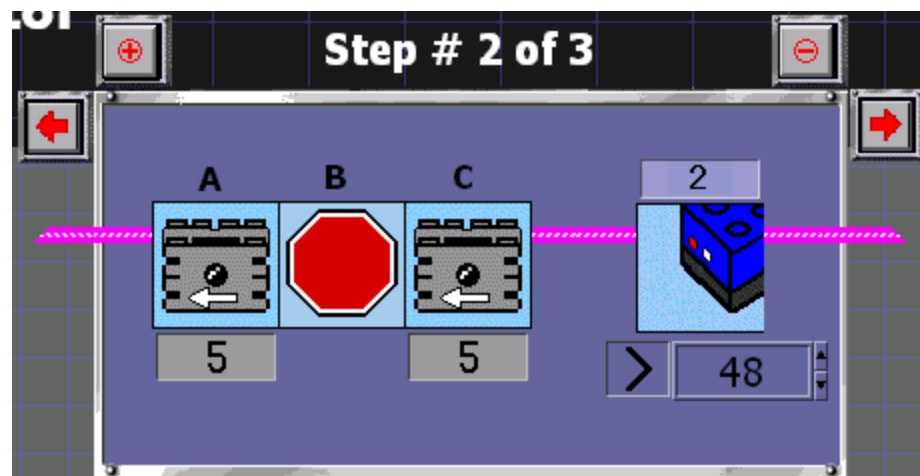
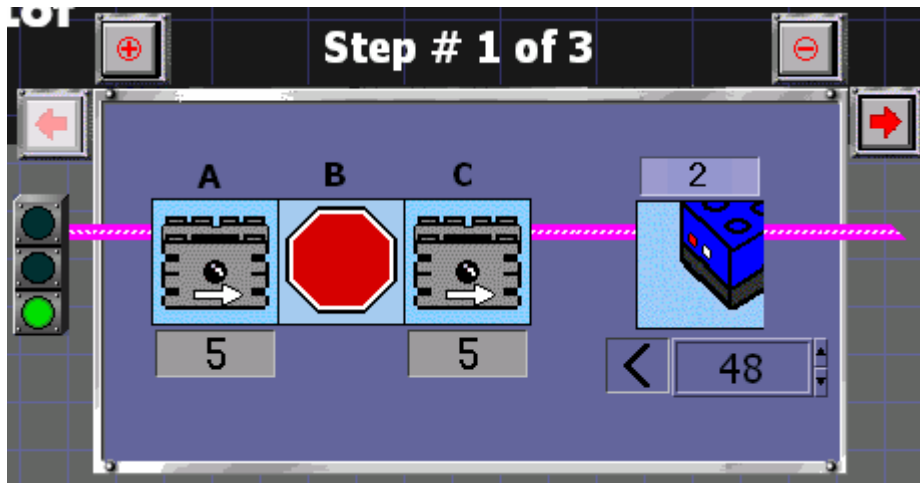
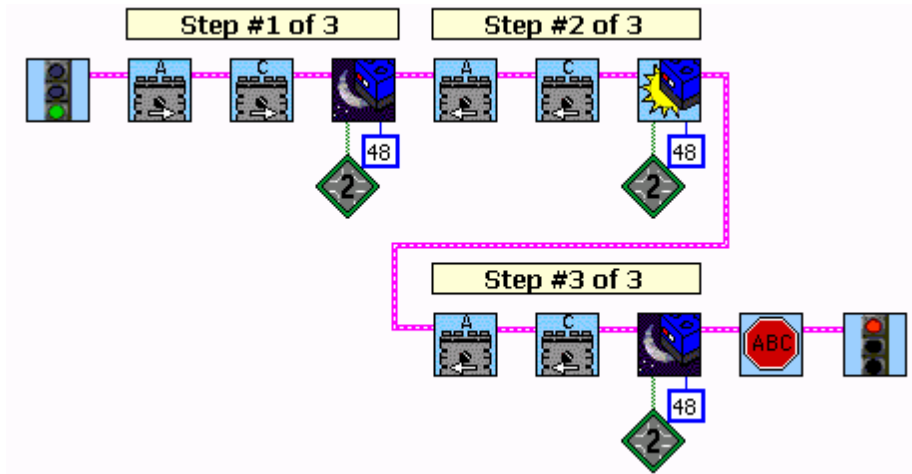


# There and Back: Using Light Sensor

Pilot version:



Inventor version:



This program makes the Robot go forward until the Light Sensor on Input Port 2 is reads a value below 48 indicating the Robot has reached the limit line. It then reverses the motors until the Light Sensor on Input Port 2 is reads a value above 48 (this is to get the sensor back off the line it just found). It continues in reverse until the Light Sensor on Input Port 2 is reads a value below 48 indicating the Robot has reached the start line, then it stops all Output Ports.

The program below is functionally equivalent to the one above but demonstrates that in Inventor the Output Ports do not change just because a Sensor Event took place unless the program specifies a change. Notice that between the Step 2 Sensor Event and Step 3 Sensor Event there are no motor icons; the motor icons prior to the Step 2 Sensor Event are still in effect so there is no need to add additional motor icons as was the case in the Pilot version of the program.

