```
Config
Globals
BEGIN        void main ( void )
Variables    {

x=1+2        x = 0 ;

[icon]       bumper = GetDigitalInput ( 1 ) ;  // read bumper value

[icon]       LLS = GetDigitalInput ( 2 ) ;  // read left limit switch

[icon]       RLS = GetDigitalInput ( 3 ) ;  // Read right limit switch

WHILE   {    while ( LLS + RLS == 2 )  // while limit switches are untriggered
             {

        [icon]   SetMotor ( 1 , 50 ) ;  // forward

        [icon]   SetMotor ( 9 , 50 ) ;  // forward

        [icon]   SetMotor ( 2 , -50 ) ;  // forward

        [icon]   SetMotor ( 10 , -50 ) ;  // forward

        [icon]   bumper = GetDigitalInput ( 1 ) ;  // read bumper value

        IF   {   if ( bumper == 0 )  // if bumper pressed
                 {

            x=1+2   x ++  ;  // add 1 to x

            [icon]  PrintToScreen ( "x value =%d\n" , x ) ;

            x%y     z = Fmod ( x , 2 ) ;  // put z as remainder value

            IF   {   if ( z > 0 )  // if bumper pressed
                     {

                [icon]  PrintToScreen ( "z value%d\n" , z ) ;

                [icon]  SetMotor ( 1 , 50 ) ;  // motor 1 forward

                [icon]  SetMotor ( 9 , 50 ) ;  // motor 9 forward

                [icon]  SetMotor ( 2 , 50 ) ;  // motor 2 reverse

                [icon]  SetMotor ( 10 , 50 ) ;  // motor 10 reverse

                [icon]  Wait ( 750 ) ;  // wait 750

                [icon]  SetMotor ( 2 , -50 ) ;  // forward

                [icon]  SetMotor ( 10 , -50 ) ;  // forward

                [icon]  Wait ( 250 ) ;  // wait 250

                [icon]  SetMotor ( 2 , 50 ) ;  // reverse

                [icon]  SetMotor ( 10 , 50 ) ;  // reverse

                [icon]  Wait ( 600 ) ;  // wait 600

                 }   }

            ELSE {   else
                     {

                [icon]  SetMotor ( 1 , -50 ) ;  // motor 1 reverse

                [icon]  SetMotor ( 9 , -50 ) ;  // motor 9 reverse

                [icon]  SetMotor ( 2 , -50 ) ;  // motor 2 forward

                [icon]  SetMotor ( 10 , -50 ) ;  // motor 10 forward

                [icon]  Wait ( 750 ) ;  // wait 750

                [icon]  SetMotor ( 1 , 50 ) ;  // forward

                [icon]  SetMotor ( 9 , 50 ) ;  // forward

                [icon]  Wait ( 250 ) ;  // wait 250

                [icon]  SetMotor ( 1 , -50 ) ;  // reverse

                [icon]  SetMotor ( 10 , -50 ) ;  // reverse

                [icon]  Wait ( 600 ) ;  // wait 600

                 }   }

        }   }

        [icon]   LLS = GetDigitalInput ( 2 ) ;

        [icon]   RLS = GetDigitalInput ( 3 ) ;

    }   }

[icon]  SetMotor ( 1 , 0 ) ;  // motor 1 stop

[icon]  SetMotor ( 2 , 0 ) ;  // motor 2 stop

[icon]  SetMotor ( 9 , 0 ) ;  // motor 9 stop

[icon]  SetMotor ( 10 , 0 ) ;  // motor 10 stop

END   }
```