```c
#include "Main.h"
void main ( void )
{
        int loop = 1;
        unsigned int UltraFront;
        unsigned int UltraBack;
        unsigned int UltraLeft;
        unsigned int UltraRight;
        int Frontleftline;
        int Frontrightline;
        int Backline;
        //Connect Input Wire to Digital Output 11
        //Connect Output wire to Interrupt 1
        // Values are in inches
        Wait ( 5000 ) ;
        while ( loop == 1 )
        {
                Frontleftline = GetAnalogInput ( 1 ) ; // get info from front left line sensor
                Frontleftline = GetAnalogInput ( 2 ) ; // get info from front right line senso¬
                r
                Backline = GetAnalogInput ( 3 ) ; // get info from back sensor
                while (  (Frontleftline  >= 250)  &&  (Frontrightline >= 250) && (Backline >= ¬
                250)  ) // While all the line sensors are good
                {
                        StartUltrasonic ( 1 , 11 ) ; // interrupt 1= output label on sensor, DO1¬
                        1=input label on sensor
                        UltraFront = GetUltrasonic ( 1 , 11 ) ;
                        PrintToScreen ( "ultrasonic =%d\n" , (int)UltraFront ) ; // for testing ¬
                        purposes only
                        if ( UltraFront <= 20 ) // if robot is less than .. inches away
                        {
                                SetDigitalOutput ( 5 , 1 ) ; // Left motor forward
                                SetDigitalOutput ( 7 , 1 ) ; // Right motor forward
                        }
                        else if ( UltraFront  > 20 ) // if front sensor doesn't see anything
                        {
                                StartUltrasonic ( 2 , 12 ) ; // Back Ultrasonic
                                StopUltrasonic ( 1 , 11 ) ; // Front Ultrasonic
                                UltraBack = GetUltrasonic ( 2 , 12 ) ;
                                if ( UltraBack  <= 20 )
                                {
                                        SetDigitalOutput ( 6 , 1 ) ; // Left motor reverse
                                        SetDigitalOutput ( 8 , 1 ) ; // Right motor reverse
                                }
                        }
                        else if ( UltraBack  > 20 ) // if back sensor doesn't see anything
                        {
                                StartUltrasonic ( 3 , 13 ) ; // Right Ultrasonic
                                StopUltrasonic ( 2 , 12 ) ; // Back Ultrasonic
                                UltraRight = GetUltrasonic ( 3 , 13 ) ;
                                if ( UltraRight  <= 20 ) // if right sensor sees robot
                                {
                                        SetDigitalOutput ( 5 , 1 ) ; // left motor foward
                                        SetDigitalOutput ( 8 , 1 ) ; // Right motor reverse
                                        while ( UltraRight <= 20 )
                                        {
                                                StartUltrasonic ( 1 , 11 ) ; // Start reading front se¬
                                                nsor while turning right
                                                UltraFront = GetUltrasonic ( 1 , 11 ) ;
                                                if ( UltraFront <= 20 ) // If front sensor sees someth¬
                                                ing
                                                {
                                                        StopUltrasonic ( 3 , 13 ) ; // Stop the right se¬
                                                        nsor
                                                        break ; // Go back to the top ...i think
                                                }
                                        }
                                }
                        }
                        else if ( UltraRight >= 20 ) // If right sensor doesn't see robot
                        {
                                StartUltrasonic ( 4 , 14 ) ; // Left Ultrasonic
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                    StopUltrasonic ( 3 , 13 ) ; // Right Ultrasonic
                    UltraLeft = GetUltrasonic ( 4 , 14 ) ;
                    if ( UltraLeft <= 20 ) // If left sensor sees robot
                    {
                            SetDigitalOutput ( 6 , 1 ) ; // Left motor reverse
                            SetDigitalOutput ( 7 , 1 ) ; // Right motor forward
                            while ( UltraLeft <= 20 ) // While left sensor sees robot
                            {
                                    StartUltrasonic ( 1 , 11 ) ; // Start reading front se¬
                                    nsor while turning right
                                    UltraFront = GetUltrasonic ( 1 , 11 ) ;
                                    if ( UltraFront <= 20 ) // If front sensor sees someth¬
                                    ing
                                    {
                                            StopUltrasonic ( 4 , 14 ) ; // Stop the left sen¬
                                            sor
                                            break ; // Go back to the top ...i think
                                    }
                            }
                    }
                    else
                    {
                            SetDigitalOutput ( 5 , 1 ) ; // Left motor forward
                            SetDigitalOutput ( 7 , 1 ) ; // Right motor forward
                            Wait ( 2000 ) ;
                            SetDigitalOutput ( 5 , 0 ) ; // Stop left motor
                            SetDigitalOutput ( 7 , 0 ) ; // Stop right motor
                            break ; // Hopefully this takes it back to the top
                    }
            }
            while (  (Frontleftline < 250) && (Frontrightline < 250)  ) // If the front li¬
            ne sensors trip
            {
                    SetDigitalOutput ( 6 , 1 ) ; // Left motor reverse
                    SetDigitalOutput ( 8 , 1 ) ; // Right motor reverse
                    Wait ( 4000 ) ;
                    SetDigitalOutput ( 5 , 0 ) ; // Stop left motor
                    SetDigitalOutput ( 7 , 0 ) ; // Stop right motor
            }
            while ( Backline < 250 ) // If the back line sensor trips
            {
                    SetDigitalOutput ( 5 , 1 ) ; // Left motor forward
                    SetDigitalOutput ( 7 , 1 ) ; // Right motor forward
                    Wait ( 4000 ) ;
                    SetDigitalOutput ( 5 , 0 ) ; // Stop left motor
                    SetDigitalOutput ( 7 , 0 ) ; // Stop right motor
            }
        }
}
```