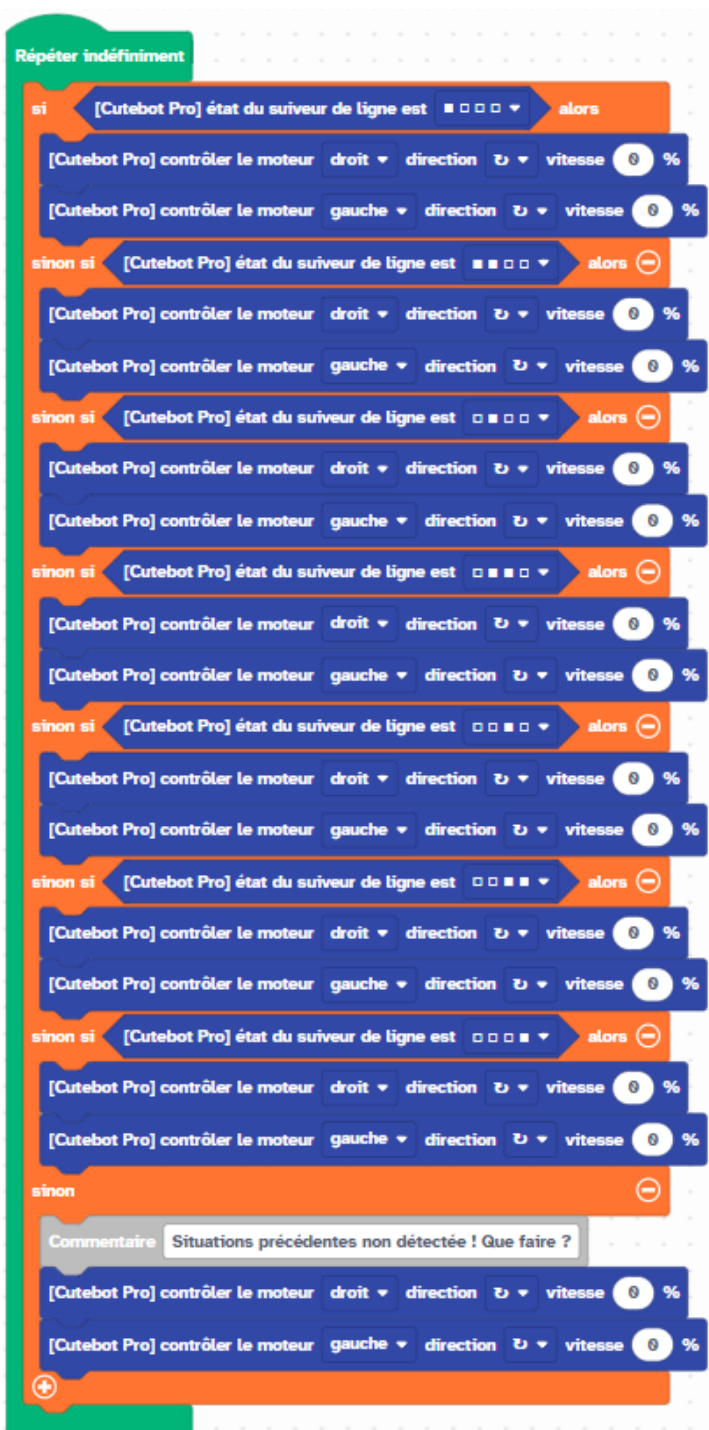




```
from microbit import *
from cutebotpro import CBP
```

```
""" Cutebot Pro robot """
```

```
CutebotPro = CBP()
```

```
display.show('Bonjour !')
```

```
while True:
```

```
    if CutebotPro.isLineTrackerState(0x01):
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_RIGHT, 0)
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_LEFT, 0)
```

```
    elif CutebotPro.isLineTrackerState(0x03):
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_RIGHT, 0)
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_LEFT, 0)
```

```
    elif CutebotPro.isLineTrackerState(0x02):
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_RIGHT, 0)
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_LEFT, 0)
```

```
    elif CutebotPro.isLineTrackerState(0x06):
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_RIGHT, 0)
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_LEFT, 0)
```

```
    elif CutebotPro.isLineTrackerState(0x04):
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_RIGHT, 0)
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_LEFT, 0)
```

```
    elif CutebotPro.isLineTrackerState(0x0C):
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_RIGHT, 0)
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_LEFT, 0)
```

```
    elif CutebotPro.isLineTrackerState(0x08):
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_RIGHT, 0)
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_LEFT, 0)
```

```
    else:
```

```
        #Situations précédentes non détectée ! Que faire ?
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_RIGHT, 0)
```

```
        CutebotPro.pwmCruiseControlMotor(CutebotPro.MOTOR_LEFT, 0)
```

Remarques :