|		
A	B	C
A	B	C
1	5	
A	C	1 2 3
2s	?	

1	2	3

- In RoboLab, loops begin with a **start of loop** icon and end with an **end of loop** icon .

- **How does a fork work?**

    - When a fork is reached in a program, one of two **branches** will be taken based on the value read from one of the robot's sensors.

    - All of the fork commands on the forks palette use the greater-than (>) or less-than-or-equal (≤) condition to determine which branch to execute. These conditions are based on a **threshold value** . If the value read by the fork's sensor is greater than the threshold value, then the program follows the top branch. Otherwise, if the value read by the fork's sensor is less than or equal to the threshold value, then the program follows the bottom branch. For example, RoboLab can let a program make a decision depending on the value it gets from the **light sensor** when you use the **light sensor fork** .

    - You must attach the correct port number modifier (i.e., port 1 , port 2 or port 3) to the fork where your actual sensor is conncected.

    - A **fork merge** is required at some point in the program with any fork command. It completes your conditional structure and brings the two branches of the program back together.