Module 5 - Exercise 1 Program: This program will have the Roomba drive forward until a virtual wall is detected. Once the wall is detected, the Roomba will stop and the program will print the localized position.

```java
import roomba.roombanetwork.services.userservice.*;

public class MyRoombaProgram{

    public static void main(String[] args){
        UserService.setServerAddress("localhost");
        UserService.setName("Your Name");

        Roomba roomba = new Roomba();

        roomba.forwardSpeed(.3);
        roomba.waitForVirtualWall();
        roomba.forwardSpeed(0);
        try{
            Thread.sleep(1000);
        } catch (Exception e){
        }
        System.out.println("X Position: \" +
                          roomba.getLocalizedX ( ) );
        System.out.println("Y Position: \" +
                          roomba.getLocalizedY ( ) );
    }
}
```
Module 5 - Exercise 2 Program: This program will have the Roomba drive in a 1 meter square 10 times. It will print the odometry position and the localized position continuously every 1 second.

```java
import roomba.roombanetwork.services.userservice.*;

public class MyRoombaProgram{
    public static void main(String [] args){
        UserService.setServerAddress("localhost");
        UserService.setName("Your Name");

        Roomba roomba = new Roomba();

        for (int i=0;i<40;i++){
            roomba.drive(1);
            roomba.turn(90);
        }

        while (true){
            System.out.println("X Odometry Position: "+roomba.getOdometryX());
            System.out.println("Y Odometry Position: "+roomba.getOdometryY());
            System.out.println("X Localized Position: "+roomba.getLocalizedX());
            System.out.println("Y Localized Position: "+roomba.getLocalizedY());

            try{
                Thread.sleep(1000);
            } catch (Exception e){
                
            }
        }
    }
}
```