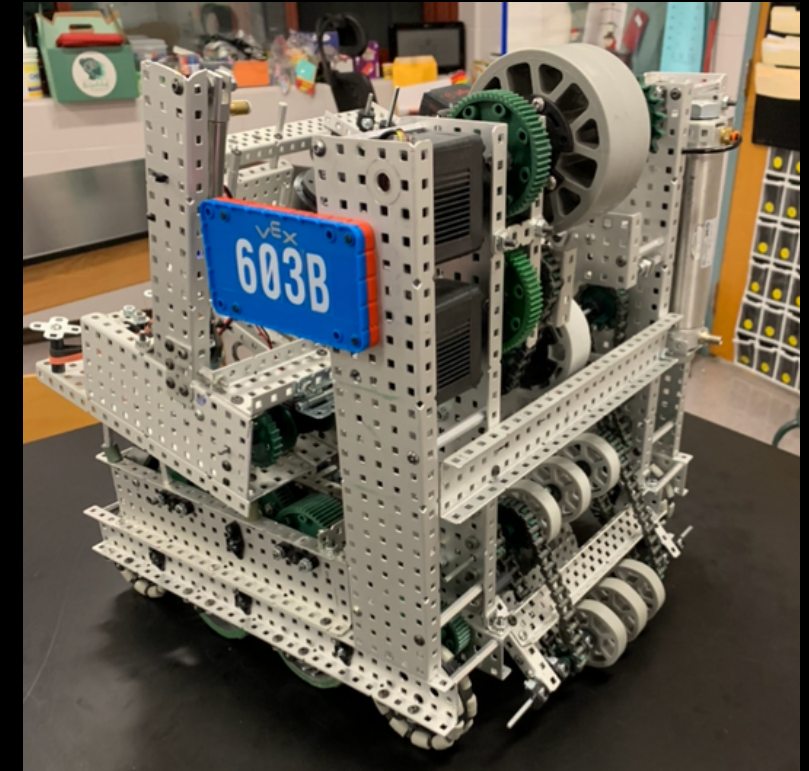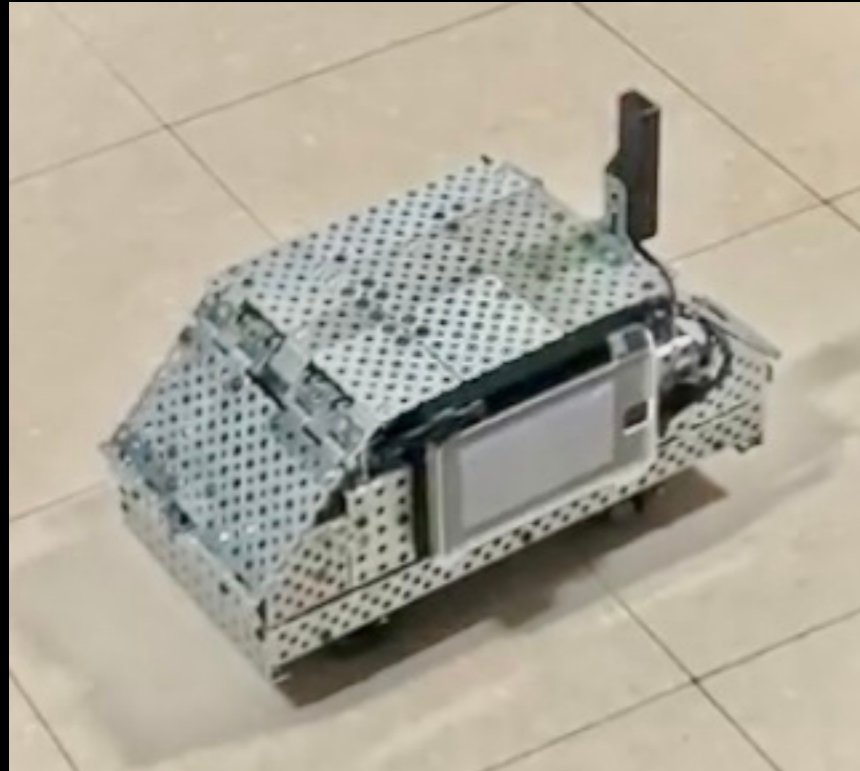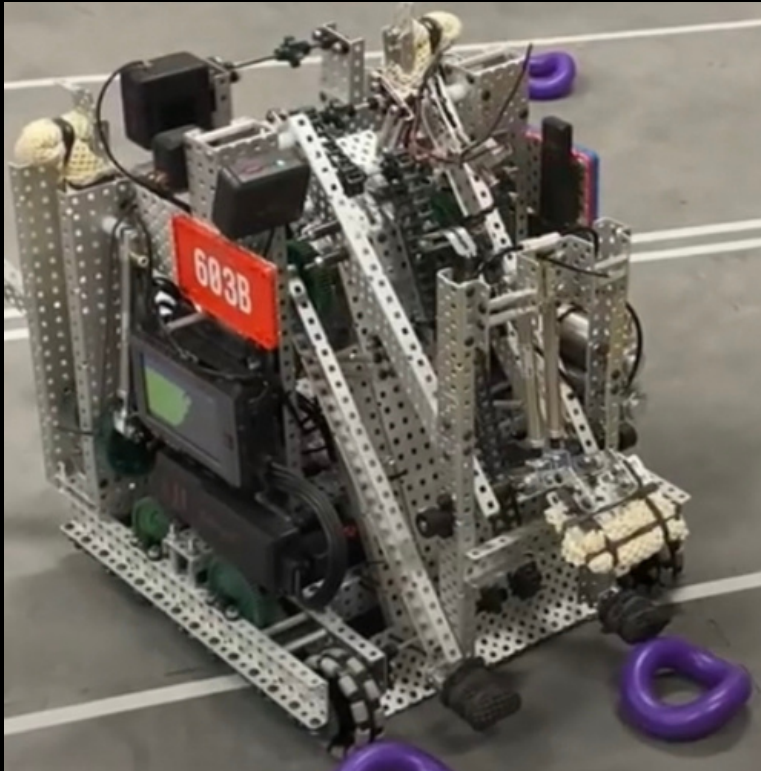# Join The Robo Raiders

Build your own robots

Program your robots

```
92   /*Robot I Don't Know (IDK) is positioned in the RED FRONT SCORING ZONE.
93   Goal is to score 1 point in the Goal Zone. IDK is positioned on the field
94   with ORANGE pre-load cube touching FRONT side of robot.
95   */
96
97   //STEP 1: IDK will grab pre-load and position itself over 1st cube
98       Claw.rotateFor(1.5, rev, 100, vex::velocityUnits::pct);
99       Claw.spin(vex::fwd, 10, vex::velocityUnits::pct);
100      wait(300, msec);
101      LiftMotors.rotateFor(Hotdog, rev, 100, vex::velocityUnits::pct);
102      robot.driveFor(4.5, inches, 30, vex::velocityUnits::pct);
103      wait(200, msec);
104
105
106  //STEP 2: IDK will stack onto 2nd cube
107      //Drop Stack
108          Claw.rotateFor(-.3, rev, 90, vex::velocityUnits::pct);
109          LiftMotors.rotateFor(-Hotdog, rev, 100, vex::velocityUnits::pct);
110          robot.driveFor(HawaiianPizza, inches, 30, vex::velocityUnits::pct);
111          wait(200, msec);
112      //Pick up new Stack (2)
113          Claw.rotateFor(.3, rev, 100, vex::velocityUnits::pct);
114          Claw.spin(vex::fwd, 10, vex::velocityUnits::pct);
115          wait(300, msec);
116          //robot.driveFor(-HawaiianPizza, inches, 42, vex::velocityUnits::pct);
117          LiftMotors.rotateFor(Hotdog, rev, 85, vex::velocityUnits::pct);
118
```
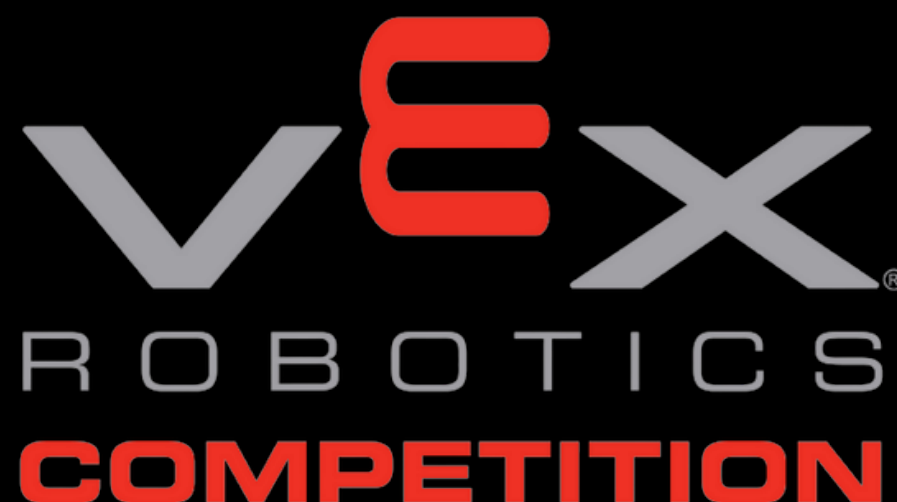
```
108  double turnImportant = 1;
109
110  while (1) {
111      double turnVal = Controller1.Axis4.position(percent);
112      double forwardVal = Controller1.Axis3.position(percent);
113      double turnVolt = turnVal * 0.12;
114      double forwardVolt = forwardVal * 0.12 * (1 - (std::abs(turnVolt)/12.0) * turnImportant);
115
116      LD.spin(forward, forwardVolt - turnVolt, voltageUnits::volt);
117      RD.spin(forward, forwardVolt + turnVolt, voltageUnits::volt);
118
119      //Intake
120      if(Controller1.Axis2.position() > 50){
121          Intake.spin(forward, 100, pct);
122      }
123
124      else if (Controller1.Axis2.position() < -50){
125          Intake.spin(forward, -100, pct);
126      }
127
128      else{
129          Intake.stop(coast);
130      }
131
132
133      //Catapult
134      if(Controller1.ButtonL1.pressing() > 0 && Rotate.position(degrees) < 71){
135          Catapult.spin(reverse, 100, pct);
136      }
137
138      else if(Controller1.ButtonL2.pressing()){
139          Catapult.spin(forward, 100, pct);
140      }
```

Compete against other teams around the state

THE WAVE

VEX ROBOTICS COMPETITION

Robot Events

Vex.com

Facebook