V^E×CODE VR

Student Name: Darren

Assignment: Vexcode Vr Skills challenge - Elementary

Notes: From Team 8391Z - Caution Tape Robotics, Markham Ontario Canada

Playground: VIQC Virtual Skills - Full Volume

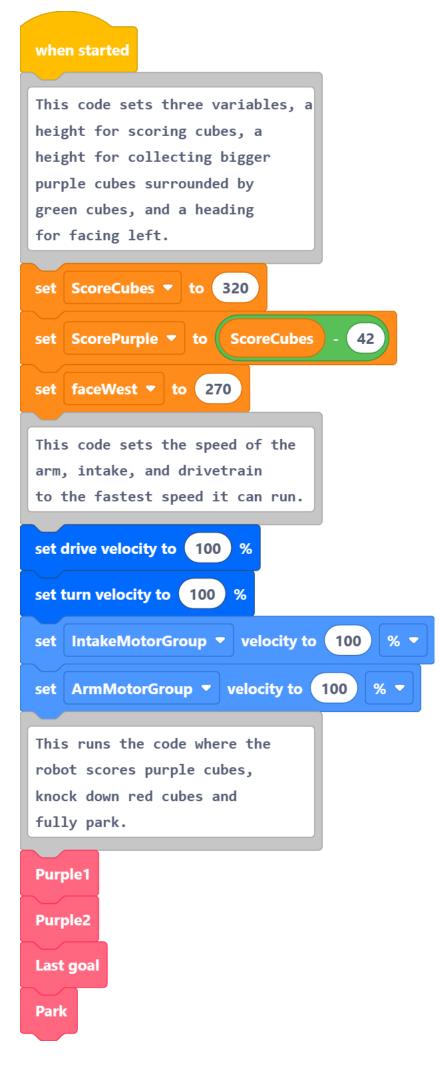
Project Name: My project

Project Type: Blocks

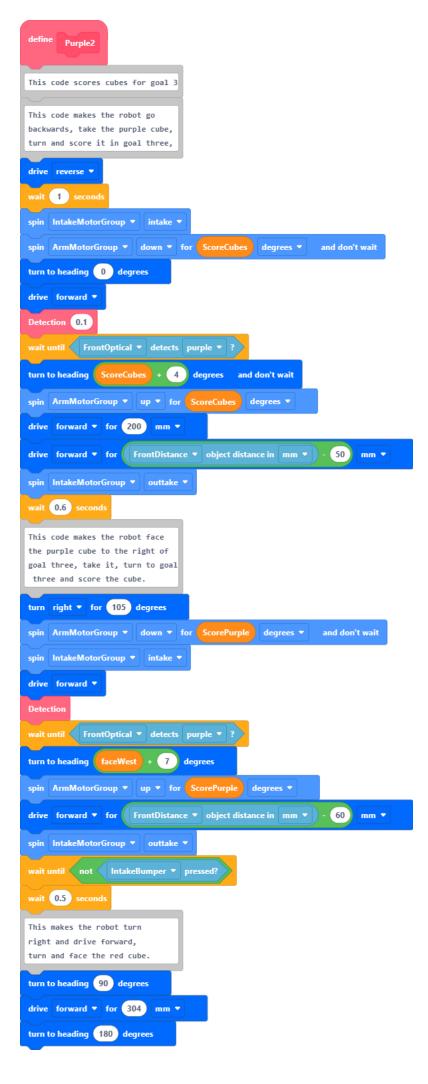
Date: Fri Jan 05 2024







define Purple1
This code scores cubes for Goal 2
This turns to robot to face a purple cube at 45 degree heading, take it, turn around, drive to goal two, face left and score it.
turn to heading 45 degrees
spin IntakeMotorGroup 🔹 intake 💌
drive forward 🔻
Detection 0.01
wait until FrontOptical 👻 detects purple 💌 ?
turn left 🔻 for 185 degrees
spin ArmMotorGroup 🔻 up 🔻 for ScoreCubes degrees 👻
drive forward 🔻 for FrontDistance 🔻 object distance in mm 🔻 - 20 mm 🔻
turn to heading faceWest degrees
drive forward 🔻 for 10 mm 💌
spin IntakeMotorGroup 🔻 outtake 💌
wait 0.6 seconds
This part makes the robot face forward, drive forward, turn while intaking the purple cube between goal two and three.
turn to heading 0 degrees and don't wait
spin ArmMotorGroup 🔻 down 🔻 for ScorePurple degrees 💌
drive forward for 20 inches
turn to heading faceWest degrees
spin IntakeMotorGroup 🔻 intake 💌
Detection 0.1
turn to heading 180 degrees and don't wait
It then face backwards, drive to goal two, turn to face left and score the cube.
spin ArmMotorGroup 🔻 up 💌 for ScorePurple degrees 💌
drive forward 🔻 for FrontDistance 🔻 object distance in mm 🔻 - 20 mm 🔻
turn to heading faceWest degrees
drive forward 🔻 for (FrontDistance 🔻 object distance in mm 💌 - 50 mm 💌
spin IntakeMotorGroup v outtake v
wait 0.6 seconds



This is a little code that detects if the intake had found a red/green cube. It would outtake the green/red cube. If it detect a purple cube, it would stop the intake.

define Detection

c wou.	la stop the intake.
orever	
	FrontOptical detects red red red red red red red red
rep	eat until FrontOptical T detects purple T? and IntakeBumper T pressed?
t	urn right v for 90 degrees
s	pin IntakeMotorGroup 🔻 outtake 🔻 for 🔰 turns 👻
t	urn left v for 90 degrees
s	pin IntakeMotorGroup 🔻 intake 💌
if	FrontOptical detects purple , and IntakeBumper pressed? then
	break
else i	FrontOptical detects purple ? and IntakeBumper pressed? then
sto	p IntakeMotorGroup 🔻
bre	ak
else	
spi	n IntakeMotorGroup 🔻 intake 🔻

define Detection (Wait time)			
This is similar to the "Detection"			
function, except that there			
is a wait time in seconds imputed			
so that you don't have to wait for			
the code to be finished.			
forever			
if FrontOptical • detects red • ? or FrontOptical • detects green • ? and IntakeBumper • pressed? then			
repeat until FrontOptical detects purple , and IntakeBumper pressed?			
turn right v for 90 degrees			
spin IntakeMotorGroup 🔻 outtake 🔻 for 🔰 turns 💌			
turn left for 90 degrees			
spin IntakeMotorGroup ▼ intake ▼			
if FrontOptical detects purple and IntakeBumper pressed? then			
break			
else if FrontOptical 🔻 detects purple 💌 ? then			
wait Wait time seconds			
stop IntakeMotorGroup 🔻			
break			
else			
spin IntakeMotorGroup 🔻 intake 🔻			



