

```

{"mode":"Text","textContent":"#region VEXcode Generated Robot
Configuration\nimport math\nimport random\nfrom vexcode_vrc import
*\nfrom vexcode_vrc.events import get_Task_func\n\n# Brain should be
defined by default\nbrain=Brain()\n\n drivetrain =
Drivetrain(\n"drivetrain", 0)\narm_motor = Motor(\n"ArmMotor",
3)\nrotation = Rotation(\n"Rotation", 7)\nintake_motor =
Motor(\n"IntakeMotor", 8)\noptical = Optical(\n"Optical", 11)\ngps =
GPS(\n"GPS", 20)\n\n#endregion VEXcode Generated Robot
Configuration\nmyVariable = 0\nArmMotorStop = False\nkmk1 = False\n\nndef
DropAcorn():\n    global myVariable, ArmMotorStop, kmk1\n
arm_motor.spin(FORWARD)\n    wait(3, SECONDS)\n
intake_motor.spin(REVERSE)\n    wait(2, SECONDS)\n    arm_motor.stop()\n
intake_motor.stop()\n    # Simplified Procedure To Drop Acorn\n\nndef
PickUpAcorn():\n    global myVariable, ArmMotorStop, kmk1\n
arm_motor.spin(FORWARD)\n    wait(3, SECONDS)\n
intake_motor.spin(FORWARD)\n    wait(2, SECONDS)\n    arm_motor.stop()\n
intake_motor.stop()\n    # Simplified Procedure To Pick Up Acorn\n\nndef
when_started1():\n    global myVariable, ArmMotorStop, kmk1\n
drivetrain.set_drive_velocity(150, PERCENT)\n
drivetrain.set_drive_velocity(150, PERCENT)\n
drivetrain.drive_for(FORWARD, 500, MM)\n
drivetrain.turn_to_heading(90, DEGREES)\n
drivetrain.drive_for(FORWARD, 1000, MM)\n
drivetrain.turn_to_heading(0, DEGREES)\n    drivetrain.drive_for(REVERSE,
350, MM)\n    DropAcorn()\n    # Drop Pre Load\n    wait(1, SECONDS)\n
arm_motor.spin(REVERSE)\n    # Positioning\n
drivetrain.turn_for(RIGHT, 90, DEGREES)\n
drivetrain.drive_for(FORWARD, 250, MM)\n    drivetrain.turn_for(LEFT, 90,
DEGREES)\n    drivetrain.drive_for(FORWARD, 510, MM)\n
drivetrain.drive_for(REVERSE, 430, MM)\n    drivetrain.turn_for(RIGHT,
90, DEGREES)\n    PickUpAcorn()\n    # Picking Up New Acorn\n
drivetrain.turn_for(LEFT, 90, DEGREES)\n    drivetrain.drive_for(FORWARD,
200, MM)\n    DropAcorn()\n    # Drop Said Acorn After Rotation\n
wait(1, SECONDS)\n    arm_motor.spin(REVERSE)\n    wait(3, SECONDS)\n
drivetrain.drive_for(FORWARD, 200, MM)\n    drivetrain.drive_for(REVERSE,
300, MM)\n    drivetrain.turn_for(LEFT, 90, DEGREES)\n
drivetrain.drive_for(FORWARD, 200, MM)\n    drivetrain.turn_for(LEFT, 90,
DEGREES)\n    drivetrain.drive_for(FORWARD, 300, MM)\n    # Quick
Commands For Extra Acorns\n    PickUpAcorn()\n    wait(2, SECONDS)\n
drivetrain.drive_for(FORWARD, 200, MM)\n    DropAcorn()\n
arm_motor.spin(REVERSE)\n    wait(2, SECONDS)\n
drivetrain.turn_for(LEFT, 90, DEGREES)\n    drivetrain.drive_for(FORWARD,
200, MM)\n    PickUpAcorn()\n    drivetrain.turn_for(RIGHT, 90,
DEGREES)\n
DropAcorn()\n\nvr_thread(when_started1)\n", "textLanguage": "python", "rconf
ig": [], "slot": 0, "platform": "PG", "sdkVersion": "20220726.10.00.00", "appVers
ion": "", "minVersion": "3.0.0", "fileFormat": "1.0.1", "icon": "", "targetBrainG
en": "First", "v5SoundsEnabled": false, "playground": "VRC24", "robotModel": "vr
c24"}

```