

Title: Flash Dragon

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Team number: 67890A

Location: Taiwan

We got to know that 67890B team get 66 points in VR because they put 2 green blocks into every basket and partial parking. So, only two ways to get higher points. First, we need to get 2 full level credit. Secondly, we need to get full parking credit. So we planed:

1. To get two red blocks, putting into third basket.
2. To get every two purple blocks, putting into second and first baskets.
3. Rush into parking area as fast as robot can.

```
def when_started1():
```

Start from B point.

```
    arm_motor_group.set_position(0, DEGREES)
```

```
    drivetrain.set_drive_velocity(100, PERCENT)
```

```
    drivetrain.set_turn_velocity(100, PERCENT)
```

```
    intake_motor_group.spin(FORWARD)
```

```
    drivetrain.drive_for(FORWARD, 50, MM)
```

```
    drivetrain.turn_for(RIGHT, 45, DEGREES)
```

```
    drivetrain.drive_for(FORWARD, 100, MM)
```

Get 1st red block.

```
    drivetrain.turn_for(LEFT, 70, DEGREES)
```

```
    drivetrain.drive(FORWARD)
```

```
    wait(2.5, SECONDS)    We don't want to measure distance so we use seconds.
```

```
    drivetrain.stop()
```

```
    arm_motor_group.spin_to_position(330, DEGREES)
```

```
    drivetrain.drive_for(FORWARD, 300, MM)
```

```
    drivetrain.turn_for(LEFT, 5, DEGREES)
```

```
    intake_motor_group.spin(REVERSE)
```

Put the 1st red block into 3rd basket.

```
    wait(1, SECONDS)
```

```
    drivetrain.turn_for(RIGHT, 5, DEGREES)
```

```
    drivetrain.drive_for(REVERSE, 100, MM)
```

```
    arm_motor_group.spin_to_position(0, DEGREES)
```

```
    intake_motor_group.spin(FORWARD)
```

```
    drivetrain.turn_for(RIGHT, 125, DEGREES)
```

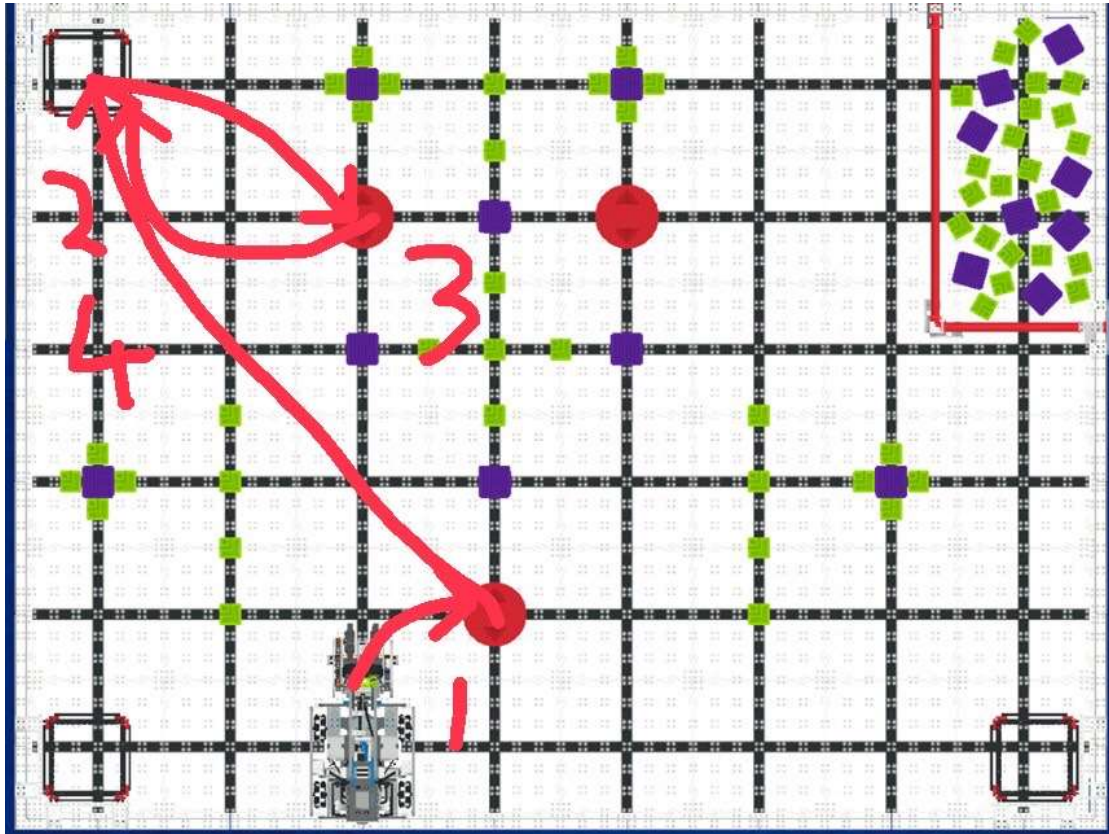
```
    drivetrain.drive_for(FORWARD, 150, MM)
```

Get 2nd red block.

```

drivetrain.drive_for(REVERSE, 150, MM)
drivetrain.turn_for(LEFT, 130, DEGREES)
arm_motor_group.spin_to_position(330, DEGREES)
drivetrain.drive_for(FORWARD, 50, MM)
intake_motor_group.spin(REVERSE) Put the 2nd red block into 3rd basket.
wait(1, SECONDS)

```



```

drivetrain.drive_for(REVERSE, 200, MM)
intake_motor_group.spin(FORWARD)
arm_motor_group.spin_to_position(0, DEGREES)
drivetrain.turn_for(RIGHT, 150, DEGREES)
drivetrain.drive_for(FORWARD, 750, MM)
Get 1st purple block and push 2nd block together.
drivetrain.turn_for(RIGHT, 110, DEGREES)
arm_motor_group.spin_to_position(330, DEGREES)
drivetrain.drive_for(FORWARD, 950, MM)
intake_motor_group.spin(REVERSE) Put the 1st purple block into 2nd basket.
wait(1, SECONDS)
drivetrain.drive_for(REVERSE, 100, MM)
intake_motor_group.spin(FORWARD)

```

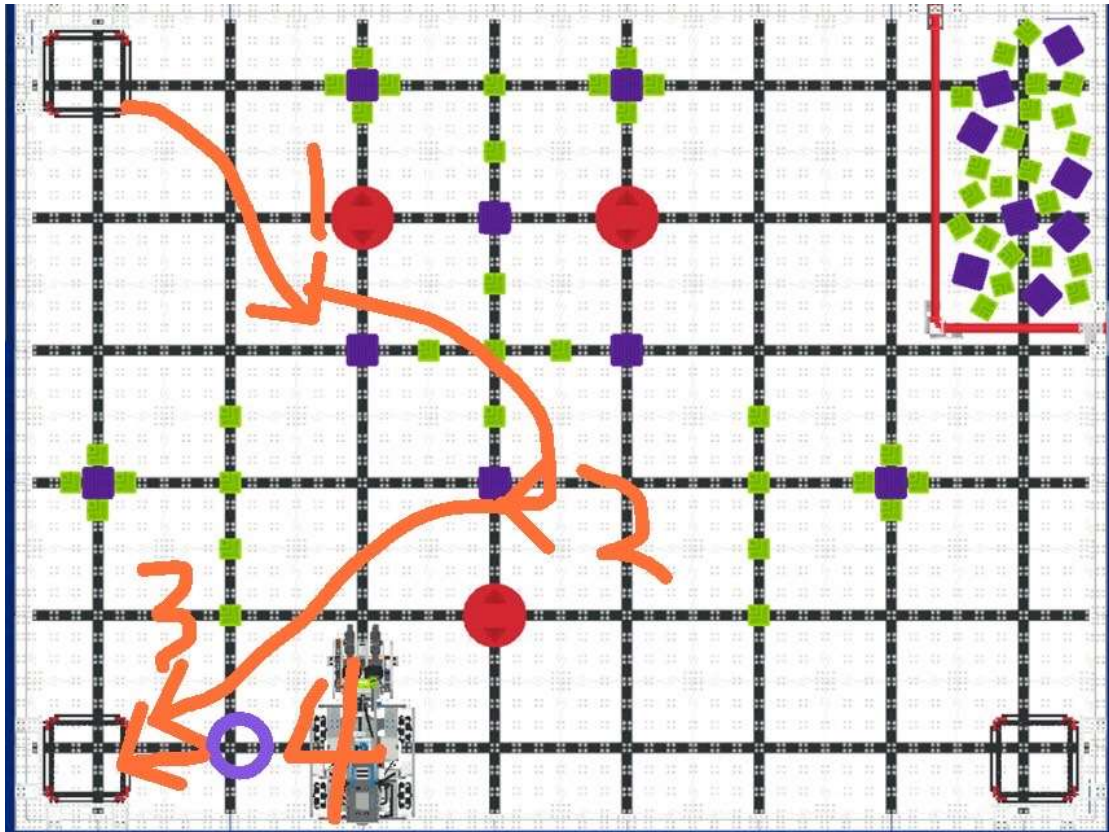
```

arm_motor_group.spin_to_position(0, DEGREES)
drivetrain.turn_for(LEFT, 20, DEGREES)
drivetrain.turn_for(RIGHT, 20, DEGREES)
arm_motor_group.spin_to_position(330, DEGREES)
drivetrain.drive_for(FORWARD, 100, MM)
intake_motor_group.spin(REVERSE)
wait(1, SECONDS)

```

2 stet to get 2nd purple block.

Put the 2nd purple block into 2nd basket.



```

drivetrain.turn_for(LEFT, 25, DEGREES)
drivetrain.drive_for(REVERSE, 900, MM)
intake_motor_group.spin(FORWARD)
arm_motor_group.spin_to_position(0, DEGREES)
drivetrain.turn_for(LEFT, 150, DEGREES)
drivetrain.drive_for(FORWARD, 200, MM)
drivetrain.turn_for(RIGHT, 20, DEGREES)
drivetrain.drive_for(FORWARD, 300, MM)
drivetrain.drive_for(REVERSE, 300, MM)
drivetrain.turn_for(RIGHT, 35, DEGREES)
arm_motor_group.spin_to_position(330, DEGREES)

```

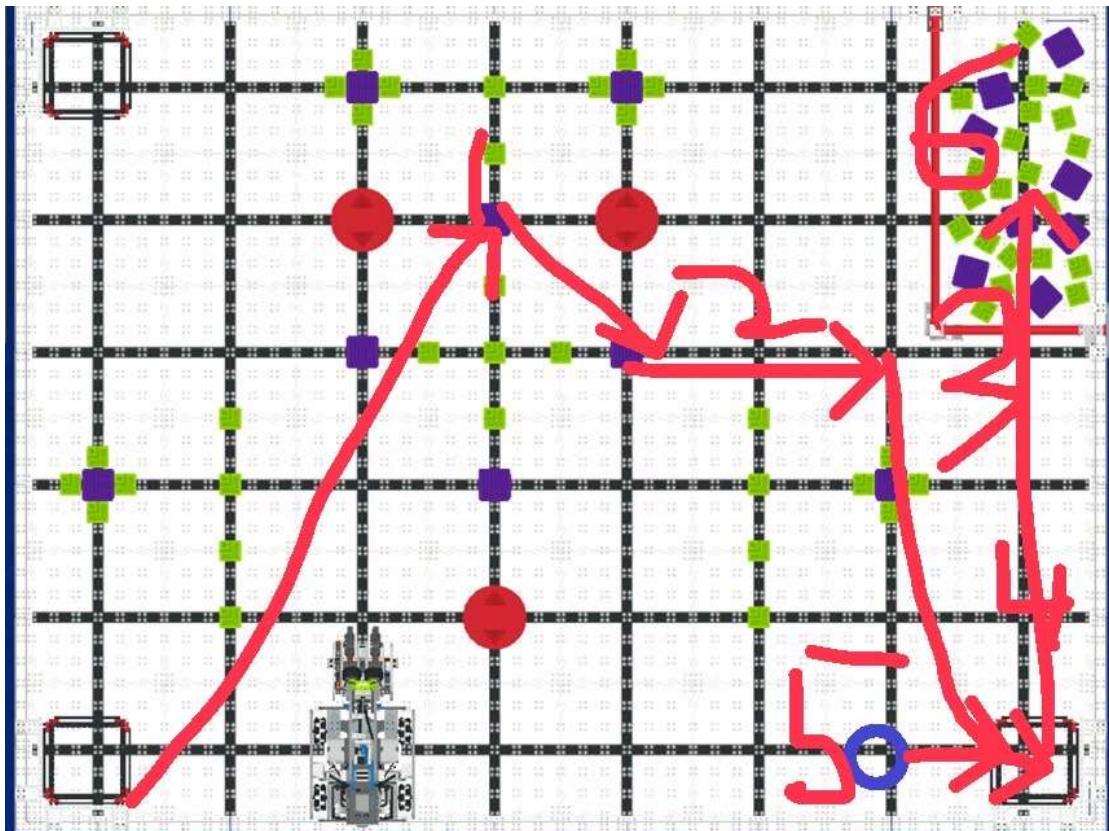
Get 1st purple block and push 2nd block together.

```

drivetrain.drive_for(FORWARD, 1000, MM)
drivetrain.turn_for(RIGHT, 50, DEGREES)
drivetrain.drive_for(FORWARD, 650, MM)
intake_motor_group.spin(REVERSE) Put the 1st purple block into 1st basket.
wait(1, SECONDS)
drivetrain.drive_for(REVERSE, 100, MM)
arm_motor_group.spin_to_position(0, DEGREES)
intake_motor_group.spin(FORWARD)
wait(0.2, SECONDS)
drivetrain.turn_for(LEFT, 10, DEGREES)
drivetrain.turn_for(RIGHT, 10, DEGREES)
drivetrain.turn_for(RIGHT, 10, DEGREES)
drivetrain.turn_for(LEFT, 10, DEGREES) 4 steps to try to get 2nd purple block.
arm_motor_group.spin_to_position(330, DEGREES)
drivetrain.drive_for(FORWARD, 20, MM)
intake_motor_group.spin(REVERSE)
wait(1, SECONDS) Put the 2nd purple block into 1st basket.
drivetrain.turn_for(LEFT, 135, DEGREES)
drivetrain.drive(FORWARD) Rush into parking area.

```

vr_thread(when_started1)



Purple Circle= The pushed purple block