

67899A

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monitor_sensor("front_distance.found_object")

def run1():
    global myVariable
    drivetrain.set_drive_velocity(100, PERCENT)
    drivetrain.set_turn_velocity(100, PERCENT)
    drivetrain.turn_to_rotation(-30, DEGREES)
    arm_motor_group.set_velocity(100, PERCENT)
    arm_motor_group.spin_to_position(0.15, TURNS, wait=False)
    intake_motor_group.set_velocity(100, PERCENT)
    drivetrain.drive_for(FORWARD, 380, MM)
    intake_motor_group.spin(FORWARD)
    arm_motor_group.spin_to_position(1, TURNS, wait=False)
    drivetrain.drive_for(REVERSE, 300, MM)
    drivetrain.turn_to_rotation(-115, DEGREES)
    intake_motor_group.spin(REVERSE)
    wait(0.5, SECONDS)
    drivetrain.turn_for(RIGHT, 165, DEGREES)
    arm_motor_group.spin_to_position(-1, TURNS, wait=False)
    intake_motor_group.spin(FORWARD)
    drivetrain.drive_for(FORWARD, 540, MM)
    arm_motor_group.spin_to_position(1, TURNS, wait=False)
    drivetrain.drive_for(REVERSE, 540, MM)
    drivetrain.turn_to_rotation(-115, DEGREES)
    drivetrain.drive_for(FORWARD, 40, MM)
    intake_motor_group.spin(REVERSE)
    wait(0.5, SECONDS)
    drivetrain.turn_to_rotation(24, DEGREES)
    arm_motor_group.spin_to_position(-1, TURNS, wait=False)
    intake_motor_group.spin(FORWARD)
    drivetrain.drive_for(FORWARD, 640, MM)
    arm_motor_group.spin_to_position(1, TURNS, wait=False)
    drivetrain.drive_for(REVERSE, 640, MM)
    drivetrain.turn_to_rotation(-115, DEGREES)
    drivetrain.drive_for(FORWARD, 40, MM)
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intake_motor_group.spin(REVERSE)
wait(0.5, SECONDS)
drivetrain.turn_to_rotation(50, DEGREES)
intake_motor_group.spin(FORWARD)
arm_motor_group.spin_to_position(-1, TURNS, wait=False)
drivetrain.drive_for(FORWARD, 1000, MM)
arm_motor_group.spin_to_position(1, TURNS, wait=False)
drivetrain.drive_for(REVERSE, 1000, MM)
drivetrain.turn_to_rotation(-115, DEGREES)
drivetrain.drive_for(FORWARD, 40, MM)
intake_motor_group.spin(REVERSE)
wait(0.5, SECONDS)
drivetrain.turn_to_rotation(70, DEGREES)
intake_motor_group.spin(FORWARD)
arm_motor_group.spin_to_position(-0.7, TURNS, wait=False)
drivetrain.drive_for(FORWARD, 400, MM)
intake_motor_group.set_velocity(50, PERCENT)
drivetrain.turn_to_rotation(-29, DEGREES)
arm_motor_group.spin_to_position(0.7, TURNS, wait=False)
drivetrain.drive_for(FORWARD, 1140, MM)
intake_motor_group.spin(REVERSE)
wait(1, SECONDS)
drivetrain.turn_to_rotation(90, DEGREES)
arm_motor_group.spin_to_position(-1, TURNS)
drivetrain.drive_for(FORWARD, 200, MM)
intake_motor_group.spin(FORWARD)
drivetrain.drive_for(REVERSE, 250, MM)
arm_motor_group.spin_to_position(0.7, TURNS, wait=False)
drivetrain.turn_for(LEFT, 105, DEGREES)
drivetrain.drive_for(FORWARD, 15, MM)
intake_motor_group.spin(REVERSE)
drivetrain.drive_for(FORWARD, 30, MM)
drivetrain.drive_for(FORWARD, 20, MM)
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def run2():
    global myVariable
    drivetrain.set_drive_velocity(100, PERCENT)
    drivetrain.set_turn_velocity(100, PERCENT)
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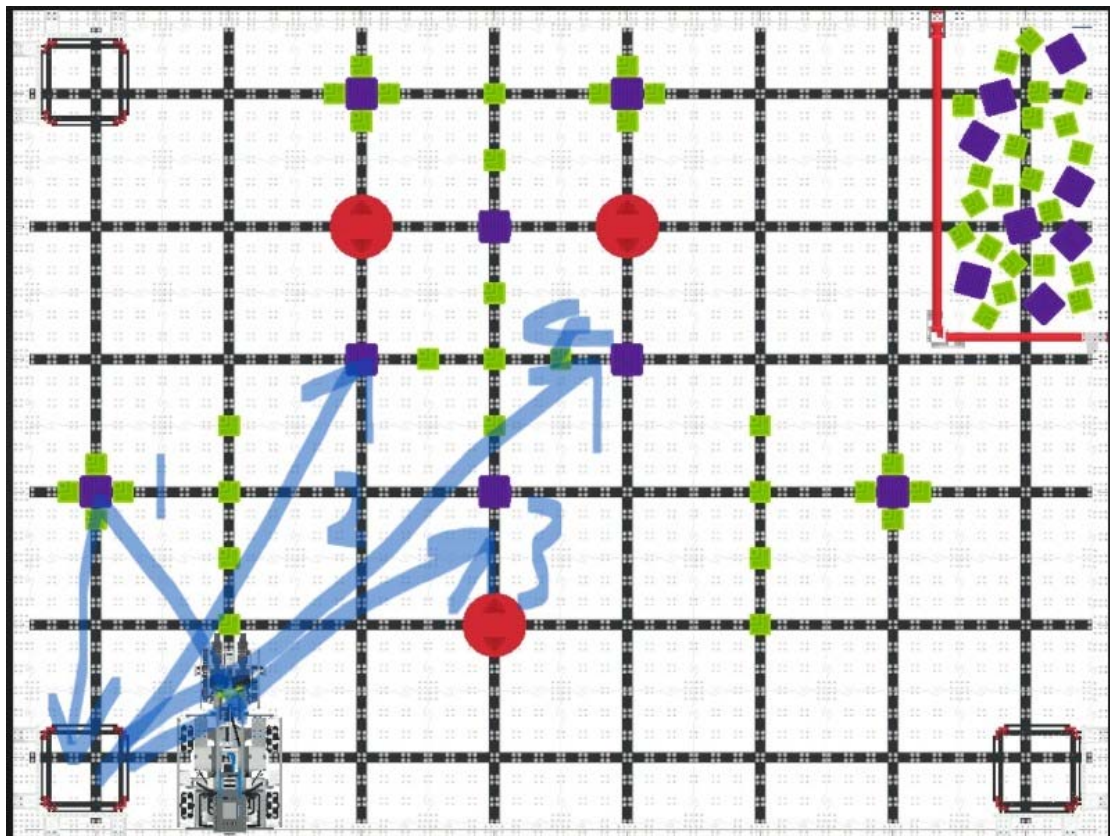
```
drivetrain.turn_to_rotation(62, DEGREES)
intake_motor_group.set_velocity(100, PERCENT)
arm_motor_group.set_velocity(100, PERCENT)
intake_motor_group.spin(FORWARD)
drivetrain.drive_for(FORWARD, 360, MM)
drivetrain.turn_to_rotation(-80, DEGREES)
drivetrain.drive_for(REVERSE, 620, MM)
drivetrain.turn_to_rotation(0, DEGREES)
drivetrain.drive_for(REVERSE, 120, MM)
drivetrain.turn_to_rotation(-225, DEGREES)
arm_motor_group.spin_to_position(1, TURNS, wait=False)
drivetrain.drive_for(FORWARD, 1380, MM)
intake_motor_group.spin(REVERSE)
wait(0.8, SECONDS)
arm_motor_group.spin_to_position(-1, TURNS, wait=False)
drivetrain.drive_for(REVERSE, 100, MM)
drivetrain.turn_to_rotation(0, DEGREES)
intake_motor_group.spin(FORWARD)
drivetrain.drive_for(FORWARD, 170, MM)
wait(0.8, SECONDS)
arm_motor_group.spin_to_position(1, TURNS, wait=False)
intake_motor_group.spin(FORWARD)
wait(0.8, SECONDS)
drivetrain.turn_to_rotation(145, DEGREES)
drivetrain.drive_for(FORWARD, 300, MM)
intake_motor_group.spin(REVERSE)
wait(0.8, SECONDS)
drivetrain.turn_to_rotation(0, DEGREES)
intake_motor_group.spin(FORWARD)
arm_motor_group.spin_to_position(0.3, TURNS, wait=False)
drivetrain.drive_for(FORWARD, 300, MM)
drivetrain.turn_for(RIGHT, 20, DEGREES)
arm_motor_group.spin_to_position(-1, TURNS, wait=False)
drivetrain.drive_for(FORWARD, 300, MM)
wait(0.8, SECONDS)
arm_motor_group.spin_to_position(1, TURNS, wait=False)
drivetrain.turn_to_rotation(180, DEGREES)
drivetrain.drive_for(FORWARD, 500, MM)
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```
intake_motor_group.spin(REVERSE)
wait(0.8, SECONDS)
drivetrain.turn_to_rotation(0, DEGREES)
drivetrain.drive_for(FORWARD, 1000, MM)
```

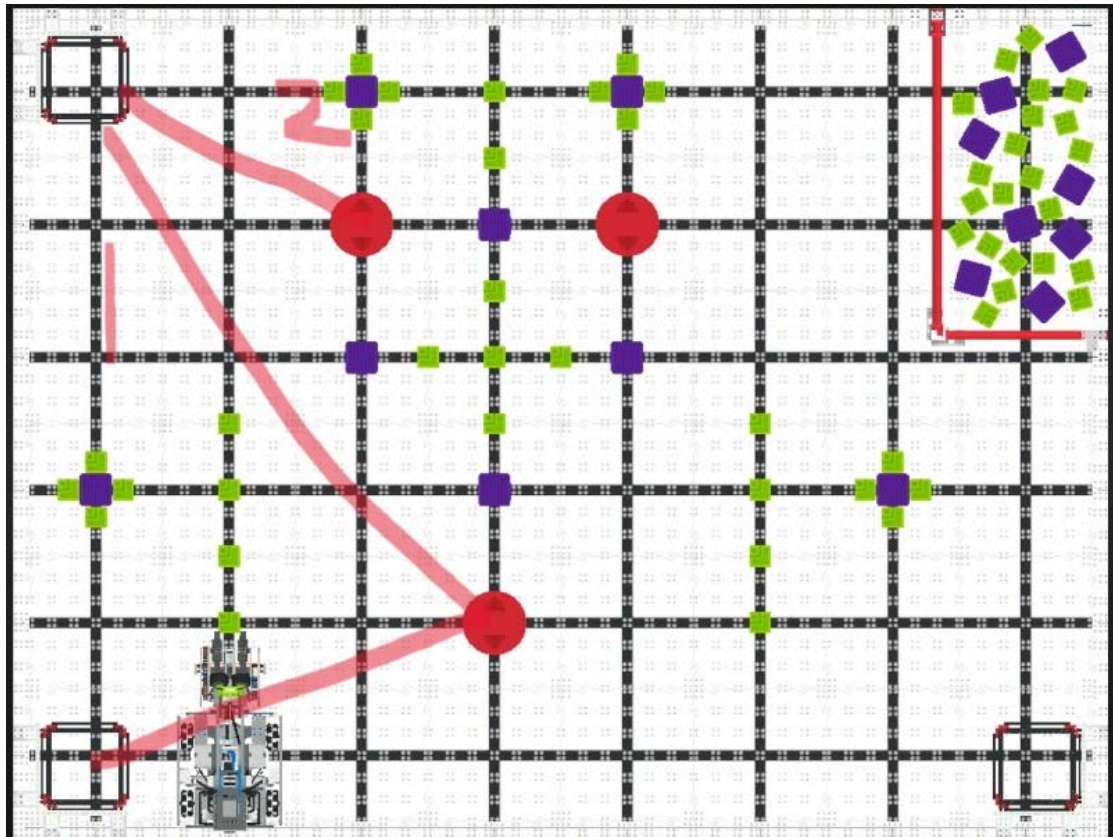
```
def when_started1():
    run1()
    wait(0.8, SECONDS)
    arm_motor_group.spin_to_position(-1, TURNS, wait=False)
    run2()
```

```
vr_thread(when_started1)
```

A



B



C

