

Student Name: Diego, Juan, Richard, Lorenzo, Jordan

Assignment: Virtual vex iq competition

Notes:

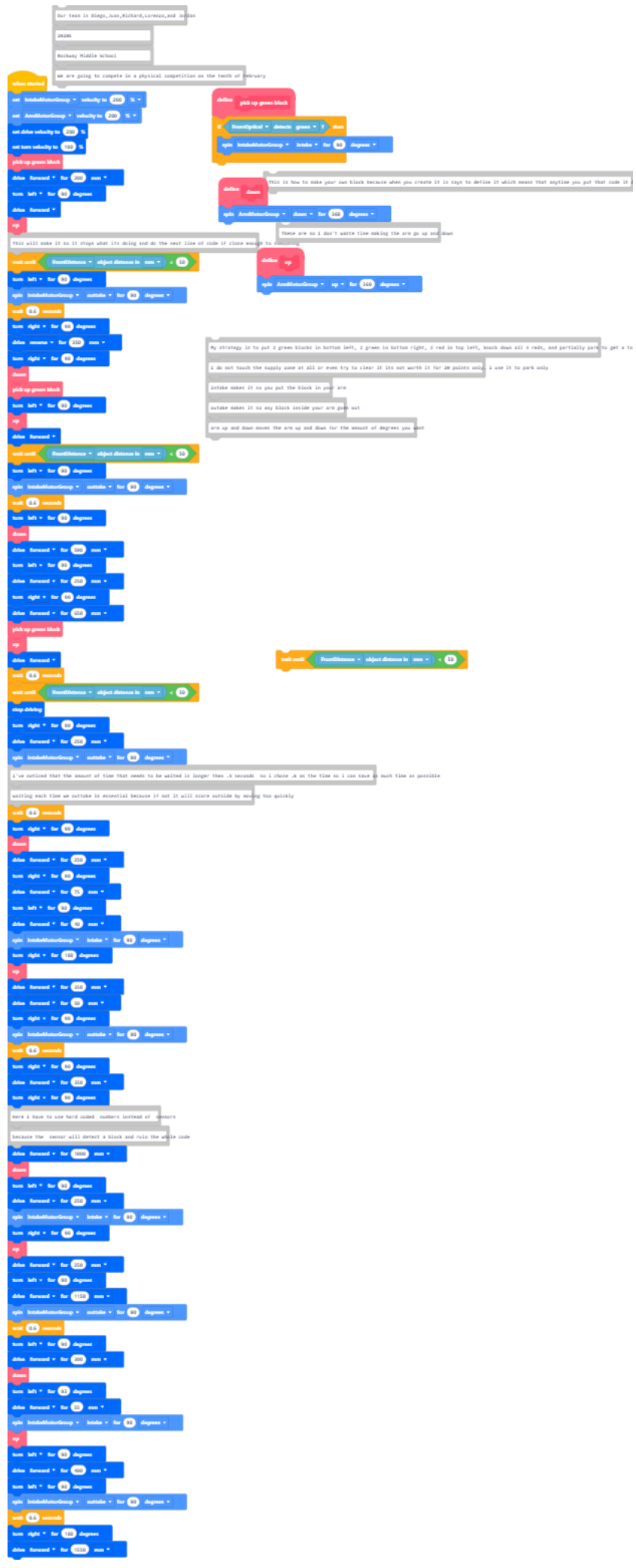
Playground: VIQC Virtual Skills - Full Volume

Project Name: 66 points finale again 3

Project Type: Blocks

Date: Thu Jan 25 2024

Playground Screenshot Not Found



Our team is Diego, Juan, Richard, Lorenzo, and Jordan

2929E

Rockway Middle School

We are going to compete in a physical competition on the tenth of F

```
when started
  set: InertiaMotorGroup * velocity to 200 %
  set: AuxMotorGroup * velocity to 200 %
  set drive velocity to 200 %
  set turn velocity to 100 %
  pick up green block
  drive forward * for 200 mm *
  turn left * for 90 degrees
  drive forward *
  stop
  This will make it so it stops what it's doing and do the next line of code if close enough to something
  wait until < FrontDistance * object distance to mm * < 20
  turn left * for 90 degrees
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  wait 0.2 seconds
  turn right * for 90 degrees
  drive reverse * for 250 mm *
  turn right * for 90 degrees
  stop
  pick up green block
  turn left * for 90 degrees
  stop
  drive forward *
  wait until < FrontDistance * object distance to mm * < 25
  turn left * for 90 degrees
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  wait 0.2 seconds
  turn left * for 90 degrees
  stop
  drive forward * for 350 mm *
  turn left * for 90 degrees
  drive forward * for 250 mm *
  turn right * for 90 degrees
  drive forward * for 550 mm *
  pick up green block
  stop
  drive forward *
  wait 0.2 seconds
  wait until < FrontDistance * object distance to mm * < 30
  stop driving
  turn right * for 90 degrees
  drive forward * for 250 mm *
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  I've noticed that the amount of time that needs to be waited is longer than .1 seconds so I chose .6 as the time so I can save
  setting each time an outtake is essential because if not it will score outside by moving too quickly
  wait 0.6 seconds
  turn right * for 90 degrees
  stop
  drive forward * for 250 mm *
  turn right * for 90 degrees
  drive forward * for 75 mm *
  turn left * for 90 degrees
  drive forward * for 40 mm *
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  turn right * for 180 degrees
  stop
  drive forward * for 350 mm *
  drive forward * for 95 mm *
  turn right * for 90 degrees
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  wait 0.2 seconds
  turn right * for 90 degrees
  drive forward * for 350 mm *
  turn right * for 90 degrees
  stop
  Here I have to use hard coded numbers instead of sensors
  because the sensor will detect a black and ruin the whole code
  drive forward * for 1000 mm *
  stop
  turn left * for 90 degrees
  drive forward * for 350 mm *
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  turn right * for 90 degrees
  stop
  drive forward * for 250 mm *
  turn left * for 90 degrees
  drive forward * for 1500 mm *
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  wait 0.2 seconds
  turn left * for 90 degrees
  drive forward * for 300 mm *
  stop
  turn left * for 90 degrees
  drive forward * for 95 mm *
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  stop
  turn left * for 90 degrees
  drive forward * for 400 mm *
  turn left * for 90 degrees
  spin: InertiaMotorGroup * velocity * for 90 degrees *
  wait 0.2 seconds
  turn right * for 180 degrees
  drive forward * for 1500 mm *
```

define

pick up green block

if detects ? then

spin intake for degrees

This is how to make your own block because when you create it it says to define it which means that anytime you put that code it d

define

down

spin

ArmMotorGroup ▼

down ▼

for

360

degrees ▼

These are so I don't waste time making the arm go up and

define up

spin ArmMotorGroup up for 360 degrees

My strategy is to put 2 green blocks in bottom left, 2 green in bottom right, 2 red in top left, knock down all 3 reds, and partially park

I do not touch the supply zone at all or even try to clear it its not worth it for 20 points only. I use it to park only

Intake makes it so you put the block in your arm

outake makes it so any block inside your arm goes out

arm up and down moves the arm up and down for the amount of degrees you want

wait until

FrontDistance ▼

object distance in

mm ▼

<

50