```
when started

set Speed ▼ to 100

set Time ▼ to 1

set Time2 ▼ to 0.1

Gets the variables set up

if < FrontDistance ▼ found an object? > then

    spin IntakeMotorGroup ▼ intake ▼

    ensures that the intake doesn't miss any objects

    if < IntakeBumper ▼ pressed? > then

        stop IntakeMotorGroup ▼

        ensures that no block gets out of the intake in case of moving in the field to score


    if < FrontOptical ▼ detects purple ▼ ? > then

        spin IntakeMotorGroup ▼ intake ▼

        Make sure that the robot only intakes purple blocks


    if < FrontOptical ▼ detects green ▼ ? > then

        spin IntakeMotorGroup ▼ outtake ▼

        Make sure that the robot only intakes purple blocks


    if < FrontOptical ▼ detects red ▼ ? > then

        spin IntakeMotorGroup ▼ outtake ▼

        Make sure that the robot only intakes purple blocks


set IntakeMotorGroup ▼ velocity to Speed % ▼

set ArmMotorGroup ▼ velocity to Speed % ▼

set turn velocity to Speed %

set drive velocity to Speed %

broadcast message1 ▼
```

```
when I receive message1
spin IntakeMotorGroup intake
drive forward for 920 mm
Intake 1 Purple Block
wait Time2 seconds
drive reverse for 860 mm
drive forward for 200 mm
turn right for 80 degrees
drive forward for 50 mm
Knock down the bottom Red Block
turn left for 170 degrees
spin ArmMotorGroup up for 300 degrees
drive forward for 350 mm
turn left for 45 degrees
drive forward for 150 mm
Angling the robot
spin IntakeMotorGroup outtake
wait Time seconds
1 Purple in Goal 2
spin IntakeMotorGroup intake
turn right for 110 degrees
spin ArmMotorGroup down for 265 degrees
drive forward for 200 mm
drive reverse for 200 mm
Angling the robot
spin ArmMotorGroup up for 265 degrees
turn left for 110 degrees
drive reverse for 10 mm
spin IntakeMotorGroup outtake
wait Time seconds
2 Purple in Goal 2
broadcast message2
```

when I receive message2

spin ArmMotorGroup down for 265 degrees

drive reverse for 50 mm

turn right for 195 degrees

spin IntakeMotorGroup intake

drive forward for 500 mm

turn left for 95 degrees

Angling the robot

spin ArmMotorGroup up for 265 degrees

drive forward for 1000 mm

spin IntakeMotorGroup outtake

wait Time seconds

1 Purple in Goal 3

turn right for 100 degrees

spin IntakeMotorGroup intake

spin ArmMotorGroup down for 260 degrees

drive forward for 300 mm

wait Time2 seconds

drive reverse for 300 mm

spin ArmMotorGroup up for 265 degrees

turn left for 100 degrees

spin IntakeMotorGroup outtake

wait Time seconds

drive reverse for 100 mm

2 Purple in Goal 3

broadcast message3

```
when I receive message3

spin ArmMotorGroup down for 251.9 degrees ▶

spin IntakeMotorGroup intake ▶

drive reverse for 400 mm ▶

turn right for 125 degrees ▶

drive forward for 700 mm ▶

turn left for 80 degrees ▶

drive forward for 100 mm ▶

Knock down the last red

drive reverse for 100 mm ▶

turn right for 120 degrees ▶

spin ArmMotorGroup up for 265 degrees ▶

drive forward for 1100 mm ▶

Angling the robot

spin IntakeMotorGroup outtake ▶

wait Time seconds

1 Purple in Goal 1

spin IntakeMotorGroup intake ▶

turn left for 141.5 degrees ▶

spin ArmMotorGroup down for 260 degrees ▶

drive forward for 270 mm ▶

wait Time2 seconds

drive reverse for 270 mm ▶

Angling the robot

spin ArmMotorGroup up for 265 degrees ▶

turn right for 145 degrees ▶

drive forward for 50 mm ▶

spin IntakeMotorGroup outtake ▶

wait Time seconds

2 Purple in Goal 1

broadcast FullyPark
```

```
when I receive  FullyPark ▾
turn  left ▾  for  100  degrees  ▶
drive  forward ▾  for  400  mm ▾  ▶
turn  left ▾  for  45  degrees  ▶
drive  forward ▾  for  200  mm ▾  ▶
turn  left ▾  for  170  degrees  ▶
drive  reverse ▾  for  20  mm ▾  ▶
stop driving
stop  IntakeMotorGroup ▾
broadcast  FullyPark ▾
```

```
when I receive  FullyPark2 ▾
spin  ArmMotorGroup ▾  up ▾  for  500  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  down ▾  for  65  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  up ▾  for  720  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  up ▾  for  500  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  down ▾  for  65  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  up ▾  for  500  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  down ▾  for  65  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  up ▾  for  720  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  up ▾  for  720  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  down ▾  for  65  degrees ▾  ▶
wait  0.001  seconds
spin  ArmMotorGroup ▾  up ▾  for  720  degrees ▾  ▶
wait  0.001  seconds
repeat  10
    spin  ArmMotorGroup ▾  down ▾  for  90  degrees ▾  ▶
    wait  0.0001  seconds
    spin  ArmMotorGroup ▾  up ▾  for  900  degrees ▾  ▶
fully parked!
```