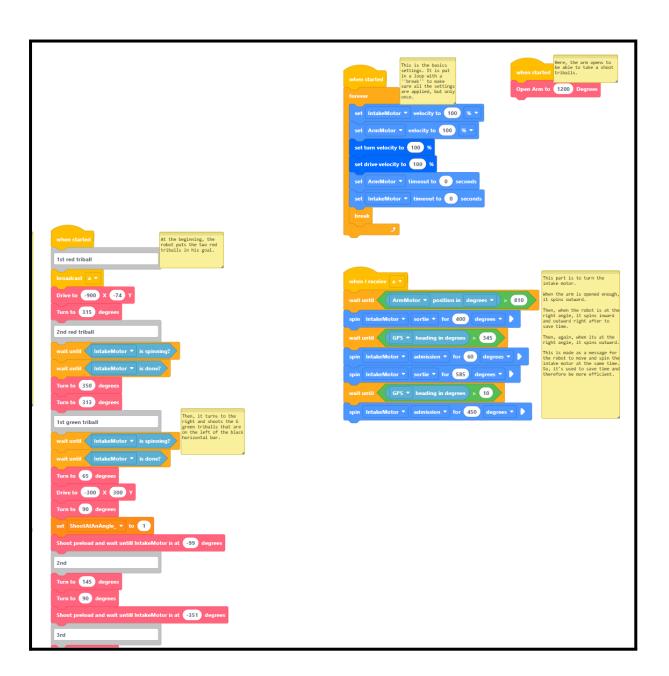
VR Skills submission - team 58676E. I'm Olivier and I'm from Quebec, Canada.

```
with a standard and standard an
```

```
define Drive bwd to 3 X 4 Y

This is also a gas evoted block, but the difference of the charge of th
```



```
Turn to 25 degrees
Turn to 90 degrees
Shoot preload and wait untill IntakeMotor is at -360 degrees
Drive to -225 X 675 Y
Drive bwd to -295 X -235 Y
Turn to 90 degrees
Shoot preload and wait untill IntakeMotor is at -108 degrees
Turn to 150 degrees
Turn to 90 degrees
Shoot preload and wait untill IntakeMotor is at -360 degrees
Drive to -200 X -675 Y
set ShootAtAnAngle_ ▼ to 0

broadcast b ▼
                                                                                   wait until
                                                                                   Drive to 650 X -500 Y
7th
                                                                                   spin IntakeMotor ▼ admission ▼ for 700 degrees ▼ ▶
Drive to 1425 X -1325 Y
                                                                                   spin IntakeMotor ▼ sortie ▼ for 625 degrees ▼ ▶
Drive to 1425 X -1100 Y
                                                                                   wait until GPS v position X v in mm v < 450

spin IntakeMotor v admission v for 50 degrees v
wait until GPS v position X v in mm v > 1150
spin IntakeMotor v sortie v for 500 degrees v b
Drive to 375 X -1400 Y
```

```
wait until GPS ▼ position X ▼ in mm ▼ > 1150
                                                                                                      spin IntakeMotor ▼ sortie ▼ for 500 degrees ▼ ▶
  Drive to 375 X -1400 Y
 Drive to 1425 X -1100 Y
                                                                                                       When I receive C V Ressage C is for the shooting loop. I wanted the robot to shoot after different number of degrees from the intake motor. So for exemple, after 233 degrees, the robot will move forward and "thoot" the tribul.
 Turn to 25 degrees
 if XYZ = 0 then
 Drive to 375 X -1400 Y
 broadcast c ▼
                                                                                                         set AngleToShoot ▼ to 233
 set ShootAtAnAngle_ ▼ to 1
                                                                                                        if XYZ = 1 then
 set TempsPourTirer ▼ to -99
 set AngleToShoot ▼ to 233
                                                                                                          set AngleToShoot ▼ to 233
                                     Later, it goes to the bottom left corner, take a triball, go to the black horizontal bar and shoot it in the goal. It does that 5 times.
 9th to 13th
 repeat 5
                                                                                                        if XYZ = 2 then
   Drive to -1375 X -1400 Y
                                                                                                          set AngleToShoot ▼ to 226
   repeat until GPS v position X v in mm v > -310
                                                                                                        if XYZ = 3 then
   drive reverse ▼
                                                                                                          set AngleToShoot ▼ to 223
                                                                                                        if XYZ = 4 then
   Turn to 90 degrees
                                                                                                           set AngleToShoot ▼ to 220
    change TempsPourTirer ▼ by -9
   change XYZ ▼ by 1
14th
                                                                                                         when I receive d 🔻
                                                                                                                                              Again, similar to message A and B, this make the intake motor spin inward or outward under specifics conditions.
```

```
set ShootAtAnAngle_ ▼ to 0
Drive to -1450 X 1400 Y
                                After, it goes to the top right corner, take a triball, shoot it in his goal, back up and the program ends.
                                                                                         stop IntakeMotor ▼
Drive to 600 X 1400 Y
                                                                                        wait until GPS ▼ position Y ▼ in mm ▼ > 1200
Drive to 1220 X 1000 Y
                                                                                        spin IntakeMotor ▼ admission ▼ for 500 degrees ▼ ▶
                                                                                         wait until GPS ▼ heading in degrees > 120
15th
spin IntakeMotor ▼ sortie ▼ for 450 degrees ▼ ▶
Drive to 1450 X 1350 Y
                                                                                         wait until GPS ▼ heading in degrees < 45
Drive to 1418 X 975 Y
                                                                                        spin IntakeMotor ▼ admission ▼ for 300 degrees ▼ ▶
Drive 125 mm -100 % speed
                                                                                         stop IntakeMotor ▼
stop project
```