By Loren Honeysuckle from team 5691A, in Bryant Arkansas.

```python
#region VEXcode Generated Robot Configuration
import math
import random
from vexcode_vrc import *
from vexcode_vrc.events import get_Task_func

# Brain should be defined by default
brain=Brain()

drivetrain = Drivetrain("drivetrain", 0)
arm_motor = Motor("ArmMotor", 3)
rotation = Rotation("Rotation", 7)
intake_motor = Motor("IntakeMotor", 8)
optical = Optical("Optical", 11)
gps = GPS("GPS", 20)

#endregion VEXcode Generated Robot Configuration
# -----------------------------------------
#
#   Project:      VEXcode Project
#   Author:       VEX
#   Created:
#   Description:  VEXcode VR Python Project
#
# -----------------------------------------




def main():

    def TARR():
        drivetrain.turn(RIGHT)
        if optical.is_near_object() :
            drivetrain.drive_for(FORWARD, 10, INCHES,wait=False)
            intake_motor.spin_for(FORWARD, 200, DEGREES)
        else:
            wait(0.1, SECONDS)
            TARR()
# This is our function which locates and picks up triballs via the optical sensor.
# "TARR" stands for Turn And Run Right


    def TARL():
        drivetrain.turn(LEFT)
        if optical.is_near_object() :
```

```python
            drivetrain.drive_for(FORWARD, 10, INCHES,wait=False)
            intake_motor.spin_for(FORWARD, 200, DEGREES)
        else:
            wait(0.1, SECONDS)




            TARL()
#This is the same as the initial function, except it turns to the left to check for
triballs.
#"TARL" Stands for Turn And Run Left.


    def BTBR():
        drivetrain.drive_for(REVERSE, 15, INCHES,wait=False)
        arm_motor.spin_for(FORWARD, 300, DEGREES)
        wait(0.25, SECONDS)
        drivetrain.turn_for(RIGHT, 70, DEGREES)
        drivetrain.drive_for(FORWARD, 11.8, INCHES)
        TARR()
        drivetrain.drive_for(REVERSE, Drive1, INCHES)
        drivetrain.turn_for(LEFT, Turn1 , DEGREES, wait=True)
        drivetrain.drive_for(FORWARD, Drive2, INCHES,wait=False)
        arm_motor.spin_for(REVERSE, 300, DEGREES, wait=False)
        wait(0.1, SECONDS)
        intake_motor.spin_for(REVERSE, 500, DEGREES)
#This is the Barrier Triball Right code.
#It is for picking up and scoring triballs on the Right of the robot on the barrier.


    drivetrain.set_turn_velocity(100, PERCENT)
    intake_motor.set_velocity(100, PERCENT)
    arm_motor.set_velocity(100, PERCENT)
    drivetrain.set_drive_velocity(100, PERCENT)
    #All velocity is set to 100 to make our robot run as quickly as possible.


    drivetrain.drive_for(FORWARD, 53, INCHES, wait=False)
    arm_motor.spin_for(FORWARD, 1800, DEGREES)
    #Adding the "wait=False" here allows these two lines to run at the same time.
    #This is used throughout or code as it is a huge timesaver and maximizes efficiency

    drivetrain.turn_for(LEFT, 20, DEGREES, wait=False)
    intake_motor.spin_for(REVERSE, 400, DEGREES)
    #End of scoring aliance triball one.
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    drivetrain.turn_for(RIGHT, 20, DEGREES)
    intake_motor.spin_for(FORWARD, 250, DEGREES)
    #End of picking up aliance triball two.
    drivetrain.turn_for(LEFT, 40, DEGREES, wait=False)
    intake_motor.spin_for(REVERSE, 400, DEGREES)
    #End of scoring aliance triball two.
    #This method and aliance triball placement was derived from team ENTER TEAM HERE

    drivetrain.drive_for(REVERSE, 10, INCHES )
    drivetrain.set_turn_velocity(70, PERCENT)
    TARR()
    #The function effectively picks up triball three.
    #Despite slight changes that can occur in the triball's placement, it will always
be picked up.
    # This is becuae the function instructs that the robot turns until an object is
detected
    drivetrain.set_turn_velocity(100, PERCENT)
    #A turn was eliminated here to maximize our time usage.
    drivetrain.drive_for(FORWARD, 17, INCHES, wait=False )
    arm_motor.spin_for(REVERSE, 300, DEGREES)
    #The arm needs to be brough slightly up in order to properly score the triball.

    drivetrain.turn_for(RIGHT, 64, DEGREES)
    drivetrain.drive_for(FORWARD, 19, INCHES, wait=False)
    wait(0.5, SECONDS)
    intake_motor.spin_for(REVERSE, 400, DEGREES)
    #End of scoring triball three, shooting from half field.
    #We discovered this strategy from team 1356B

    #This begins the NON BTBR section.
    drivetrain.drive_for(REVERSE, 16, INCHES,wait=False)
    arm_motor.spin_for(FORWARD, 300, DEGREES)
    drivetrain.set_turn_velocity(60, PERCENT)
    TARL()
    #End of picking up triball 4
    drivetrain.drive_for(REVERSE, 7, INCHES)
    drivetrain.turn_for(RIGHT, 60, DEGREES)
    drivetrain.drive_for(FORWARD, 13.5, INCHES,wait=False)
    arm_motor.spin_for(REVERSE, 300, DEGREES, wait=False)
    wait(0.5,SECONDS)
    intake_motor.spin_for(REVERSE, 500, DEGREES)
    #End of scoring triball four

    Turn1=73
    Drive1=3
    Drive2=10
    drivetrain.set_turn_velocity(60, PERCENT)
```

```python
        BTBR()
        #End of scoring triball five

        Tunr1=90
        Drive1=7
        Drive2=10
        BTBR()
        #end of scoring triballl Six

        wait(0.2,SECONDS)
        Turn1=72
        Drive1=25
        Drive2=20
        BTBR()
        #end of scoring seven

        drivetrain.drive_for(REVERSE, 12, INCHES,wait=False)
        arm_motor.spin_for(FORWARD, 300, DEGREES)
        drivetrain.turn_for(LEFT, 88, DEGREES)
        drivetrain.drive_for(FORWARD, 45, INCHES)
        TARR()
        #end of picking up triball five)
        drivetrain.drive_for(REVERSE, 35, INCHES)
        drivetrain.set_drive_velocity(50, PERCENT)
        drivetrain.turn_for(RIGHT, 65, DEGREES)
        drivetrain.drive_for(FORWARD, 25, INCHES,wait=False)
        arm_motor.spin_for(REVERSE, 300, DEGREES, wait=False)
        wait(0.25,SECONDS)
        intake_motor.spin_for(REVERSE, 500, DEGREES)
        #End of scoring triball seven

# VR threads — Do not delete
vr_thread(main)
```