
when started
set drive heading to 270 degrees
Set up Speed 100
55 point auton
define 55 point auton
spin ArmMotor down
Move To: X: -60 Y: -38
Turn to: 90
spin ArmMotor to position 180 * 8 degrees
Put ball into goal 5
Move To: X: -52 Y: -38
spin IntakeMotor intake for 80 degrees
Turn to: 115
Put ball into goal 5
Move To: X: -14 Y: -38
Turn to: 315
spin IntakeMotor intake for 80 degrees
Move To: X: 12 Y: -36
Move To: X: 36 Y: -18
Turn to: 0
Put ball into goal 5
Grab a ball to goal 10 -24
Grab a ball to goal 8 0
Grab a ball to goal -10 0
Grab a ball to goal 8 24
Grab ball from under bar 58
Grab ball from under bar -58
Match Load Long Cycle
Match Load Long Cycle
spin IntakeMotor outtake
drive reverse
spin ArmMotor up
define Move To: X Y
Using GPS to make precise movements
set x to GPS position X in inches
set y to GPS position Y in inches
set tarX to X - x
set tarY to Y - y
set tarTheta to atan2 of X: tarX Y: tarY
set dist to sqrt of tarX * tarX + tarY * tarY
turn to heading 0 - tarTheta degrees
drive forward for dist inches
define Put ball into goal number
drive forward for number inches and don't wait
spin IntakeMotor outtake for 50 * number degrees
drive reverse for number inches
define Grab a ball to goal X Y
spin ArmMotor to position 140 * 8 degrees and don't wait
Move To: X Y
spin ArmMotor to position 180 * 8 degrees and don't wait
Turn to: 180
spin IntakeMotor intake for 90 degrees
Move To: X: 36 Y: Y / 2.5
Turn to: 0
Put ball into goal 5
define Turn to: number
turn to heading 0 - number degrees
define Get triball from goal
spin ArmMotor to position 150 * 8 degrees and don't wait
Move To: X: -54 Y: -54
spin ArmMotor to position 180 * 8 degrees and don't wait
Turn to: 235
spin IntakeMotor intake for 80 degrees
define Set up Speed speed
set drive velocity to speed %
set turn velocity to speed %
set ArmMotor velocity to speed %
set IntakeMotor velocity to speed %
define Grab ball from under bar Y
Grab ball from under bar
Move reverse to: 36 Y * 0.95
Move To: X: 12 Y: Y
spin IntakeMotor intake for 90 degrees
spin ArmMotor to position 140 * 8 degrees and don't wait
Move To: X: 36 Y: Y
spin ArmMotor to position 180 * 8 degrees and don't wait
Move To: X: 36 Y: Y / 4
Turn to: 0
Put ball into goal 5
define Match Load Short Cycle
Move To: X: -44 Y: -50
Get triball from goal
spin ArmMotor to position 45 * 8 degrees and don't wait
Turn to: 30
set IntakeMotor velocity to 100 %
spin IntakeMotor outtake for 360 degrees
set IntakeMotor velocity to 50 %
spin ArmMotor to position 180 * 8 degrees and don't wait
Up
spin ArmMotor to position 0 degrees
Down
spin ArmMotor to position 180 * 8 degrees
spin IntakeMotor intake for 90 degrees
define Move reverse to: X Y
Using GPS to make precise movements
set x to GPS position X in inches
set y to GPS position Y in inches
set tarX to X - x
set tarY to Y - y
set tarTheta to atan2 of X: tarX Y: tarY
set dist to sqrt of tarX * tarX + tarY * tarY
turn to heading tarTheta degrees
drive reverse for dist inches
define Match Load Long Cycle
Move To: X: -44 Y: -50
Get triball from goal
Move To: X: 18 Y: -20
Move To: X: 36 Y: -18
Turn to: 0
Put ball into goal 5