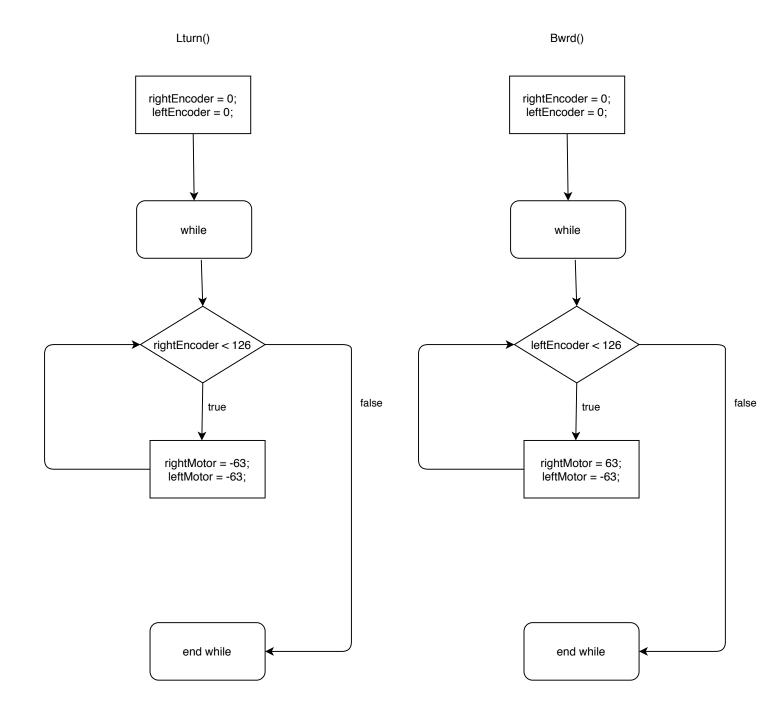
forward(t) Bwrd() rightEncoder = 0; leftEncoder = 0; while while leftEncoder < 300\*t leftEncoder > 0false false true true rightMotor = 126; leftMotor = 126; rightMotor = -80; leftMotor = 80; end while end while

Forward(1);
Backward();
Forward(2);
Backward();
Forward(3);
Backward();
Forward(4);
Backward();
Forward(5);
Backward()



F4/\.	
Fwrd(); Rturn();	
Fwrd(); Lturn();	
Fwrd(); Lturn();	
Fwrd(); Rturn();	
Fwrd(); Rturn();	
Fwrd(); Lturn();	
Fwrd(); Rturn();	
Fwrd(); Rturn();	
Fwrd(); Lturn();	
Fwrd(); Rturn();	
Fwrd(); Rturn();	
Fwrd(); Lturn();	
Fwrd(); Lturn();	
Fwrd(); Rturn();	
Fwrd();	