

SENSING ACTION WITH FUNCTIONS II

pitch

This function calculates and returns the current pitch angle of the robot in degrees. The pitch angle is the amount of rotation around the **X** axis. Positive angles indicate a rotation upwards, while negative angles indicate a rotation downwards.

yPos

This function measures and returns the **Y** coordinate of the closest mosquito to the robot. Remember that the coordinates are in relation to a fixed **X, Y, Z** axis positioned at the base of the robot. Use the coordinate system in the top right corner of the simulation to help orient yourself.

pitchSpeed(speed)

The `pitchSpeed()` function tells the robot to start rotating its aim around the **X** axis at a specified speed. A positive input rotates the robot upwards, while a negative input rotates the robot downwards (when looking at the horizon). An input of zero stops the rotation.

Math.sqrt(number)

This function will return the square root of the input number.