diagonal.rbt

```
wsl@Alex-P-Lenovo:~/textx$ python3 robot.py
Setting position to: 0, 0
Robot position is 0, 0.
Going upleft for 100 step(s).
Robot position is -100, 100.
Going upright for 100 step(s).
Robot position is 0, 200.
Going downleft for 100 step(s).
Robot position is -100, 100.
Going downright for 100 step(s).
Robot position is 0, 0.
```

noscope.rbt

```
wsl@Alex-P-Lenovo:~/textx$ python3 robot.py
Setting position to: 0, 0
Robot position is 0, 0.
Taking 3600 degrees of rotation.
Robot position is 0, 0.
Going up for 10000000 step(s).
Robot position is 0, 10000000.
```

enderman.rbt:

```
wsl@Alex-P-Lenovo:~/textx$ python3 robot.py
Setting position to: 0, 0
Robot position is 0, 0.
Going to random position in a 1 square "radius" from current position
Robot position is 1, -1.
Going to random position in a 10 square "radius" from current position
Robot position is -3, -11.
Going to random position in a 100 square "radius" from current position
Robot position is -39, -21.
Going to random position in a 1000 square "radius" from current position
Robot position is 465, 38.
Going to random position in a 10000 square "radius" from current position
Robot position is 8894, 5430.
Going to random position in a 100000 square "radius" from current position
Robot position is -36677, 53512.
Going to random position in a 1000000 square "radius" from current position
Robot position is -612394, 802804.
```