

1a

Shape Tracer

Front Eye	Down Eye	Location	Location Angle	Bumper	Distance
Object: False	Object: False	X: 572 mm	0°	Left: False	916 mm

when started

- set turn velocity to 100 %
- set drive velocity to 100 %
- set panjang to 235
- repeat 5
 - blok f panjang
 - move robot pen up
 - drive forward for 30 mm
 - turn right for 90 degrees
 - drive forward for 50 mm
 - turn left for 90 degrees
 - change panjang by -45
- stop project

define blok f sisi

- move robot pen down
- repeat 8
 - drive forward for sisi mm
 - turn right for 45 degrees

Shape Tracer

Rotation	Front Eye	Down Eye	Location	Location Angle	Bumper	Distance
1800°	Object: False	Object: False	X: -603 mm	0°	Left: False	1542 mm

when started

- set turn velocity to 100 %
- set drive velocity to 100 %
- set panjang to 190
- repeat 5
 - blok g panjang
 - move robot pen up
 - drive forward for 25 mm
 - turn right for 90 degrees
 - drive forward for 60 mm
 - turn left for 90 degrees
 - change panjang by -43
- stop project

define blok g sisi

- move robot pen down
- drive forward for sisi mm
- turn right for 90 degrees
- drive forward for sisi mm
- turn left for 90 degrees
- drive forward for sisi mm
- turn right for 90 degrees
- drive forward for sisi mm
- turn right for 90 degrees
- drive forward for sisi mm
- turn left for 90 degrees
- drive forward for sisi mm
- turn right for 90 degrees
- drive forward for sisi mm

1b

Shape Tracer

Front Eye	Down Eye	Location	Location Angle	Bumper	Distance
ect: False	Object: False	X: -903 mm	0°	Left: False	1667 mm
lor: None	Color: None	Y: -722 mm		Right: False	

```

turn right for 90 degrees
clear all rows
set keliling to 12 * 190
print keliling bangun
print keliling and set cursor to next row
set luas to 5 * 190 * 190
print luas bangun
print luas and set cursor to next row
  
```

Monitor

Sensors	
Variables	
keliling bangun 2280 luas bangun 180500	

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2

Line Detector

Front Eye	Down Eye	Location	Location Angle	Bumper	Distance
ect: True	Object: False	X: -2 mm	2°	Left: True	8 mm
lor: None	Color: None	Y: 938 mm		Right: True	

```

when started
move robot pen down
set drive velocity to 100 %
set turn velocity to 100 %
clear all rows
drive forward
repeat until LeftBumper pressed?
if DownEye brightness in %
if DownEye detects red
change red_lines by 1
set print color red
if DownEye detects green
change green_lines by 1
set print color green
  
```

Monitor

Sensors	
Variables	
total number lines:5 Number of red lines:1 Number of green lines:1 Number of blue lines:1 Number of black lines:2	

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VR

FileTUTORIALSLEARNVR BotHEXBUG

UNDOREDOFarrel T17 line ...

PLAYGROUNDSTARTSTEPSTOPSHAREFEEDBACK

Line Detector

SELECT PLAYGROUND

ACTIVITIESCLOSE

Front Eye	Down Eye	Location	Location Angle	Bumper	Distance
Object: True Color: None	Object: False Color: None	X: 403 mm Y: 938 mm	360°	Left: True Right: True	7 mm

A

B

C

D

E

when LeftBumper pressed

when started

move robot pen down

set drive velocity to 100 %

set turn velocity to 100 %

clear all rows

drive forward

repeat until LeftBumper pressed?

if DownEye brightness in %

if DownEye detects red

change red_lines by 1

set print color red

if DownEye detects green

change green_lines by 1

set print color green

if DownEye detects blue

Monitor

Sensors

Variables

ADD LISTS

total number lines:8
Number of red lines:3
Number of green lines:3
Number of blue lines:2
Number of black lines:0

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VR

FileTUTORIALSLEARNVR BotHEXBUG

UNDOREDOFarrel T17 line ...

PLAYGROUNDSTARTSTEPSTOPSHAREFEEDBACK

Code

Line Detector

SELECT PLAYGROUND

ACTIVITIESCLOSE

Front Eye	Down Eye	Location	Location Angle	Bumper	Distance
Object: True Color: None	Object: False Color: None	X: 803 mm Y: 938 mm	0°	Left: True Right: True	7 mm

A

B

C

D

E

when LeftBumper pressed

when started

move robot pen down

set drive velocity to 100 %

set turn velocity to 100 %

clear all rows

drive forward

repeat until LeftBumper pressed?

if DownEye brightness in %

if DownEye detects red

change red_lines by 1

set print color red

if DownEye detects green

change green_lines by 1

set print color green

Monitor

Sensors

Variables

ADD LISTS

total number lines:8
Number of red lines:3
Number of green lines:2
Number of blue lines:3
Number of black lines:0

CLEARSAVECOPY TO CLIPBOARD