float myVariable, state;

// "when started" hat block

int whenStarted1() {

BrainInertial.startCalibration();

while (BrainInertial.isCalibrating()) { task::sleep(50); }

state = Optical10.hue();

Motor5.setVelocity(100.0, percent);

Motor5.setMaxTorque(100.0, percent);

Drivetrain.driveFor(forward, 200.0, mm, true);

MotorGroup6.spinFor(forward, 90.0, degrees, true);

Drivetrain.turnFor(right, 90.0, degrees, true);

Drivetrain.driveFor(forward, 200.0, mm, true);

Motor5.spinToPosition(90.0, degrees, true);

return 0;

}

// "when buttonCheck pressed" hat block

void onevent\_buttonCheck\_pressed\_0() {

Motor5.spinFor(forward, 840.0, degrees, true);

}

// "when buttonLeft pressed" hat block

void onevent\_buttonLeft\_pressed\_0() {

Motor5.setVelocity(100.0, percent);

Motor5.spinFor(reverse, 50.0, degrees, true);

Motor5.spinFor(forward, 100.0, degrees, true);

}

// "when buttonRight pressed" hat block

void onevent\_buttonRight\_pressed\_0() {

Motor5.setVelocity(20.0, percent);

Motor5.spinFor(reverse, 50.0, degrees, true);

Motor5.spinFor(forward, 100.0, degrees, true);

}

// "when buttonRight released" hat block

void onevent\_buttonRight\_released\_0() {

Motor5.stop();

}

// "when buttonLeft released" hat block

void onevent\_buttonLeft\_released\_0() {

Motor5.stop();

}

int main() {

// Initializing Robot Configuration. DO NOT REMOVE!

vexcodeInit();

// register event handlers

Brain.buttonCheck.pressed(onevent\_buttonCheck\_pressed\_0);

Brain.buttonLeft.pressed(onevent\_buttonLeft\_pressed\_0);

Brain.buttonRight.pressed(onevent\_buttonRight\_pressed\_0);

Brain.buttonRight.released(onevent\_buttonRight\_released\_0);

Brain.buttonLeft.released(onevent\_buttonLeft\_released\_0);

wait(15, msec);

whenStarted1();

}