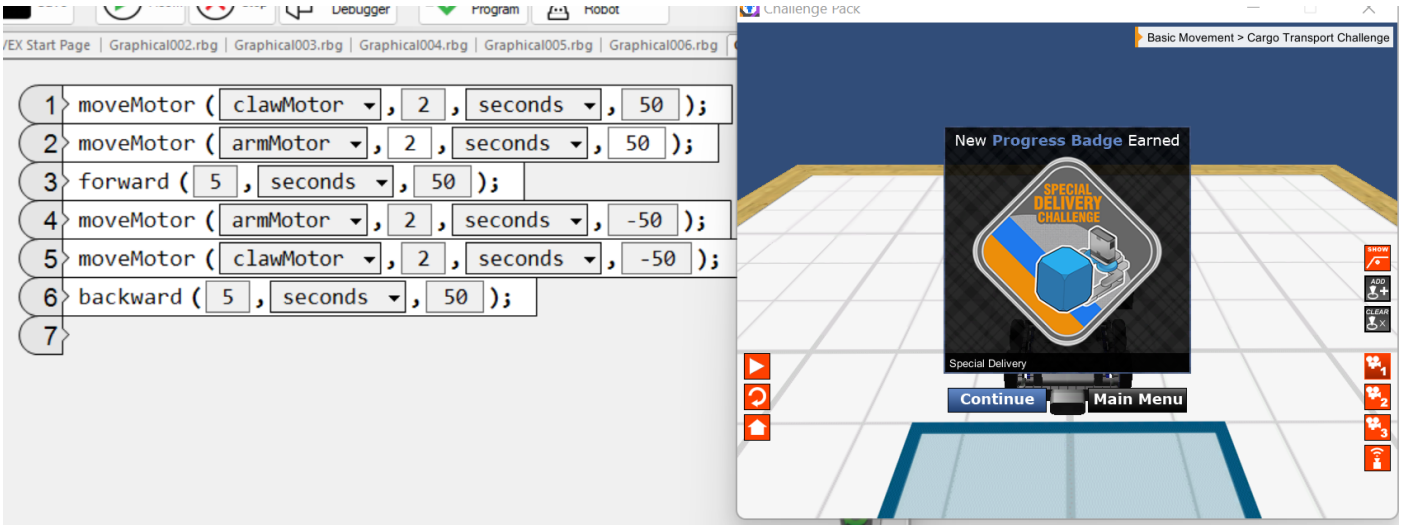
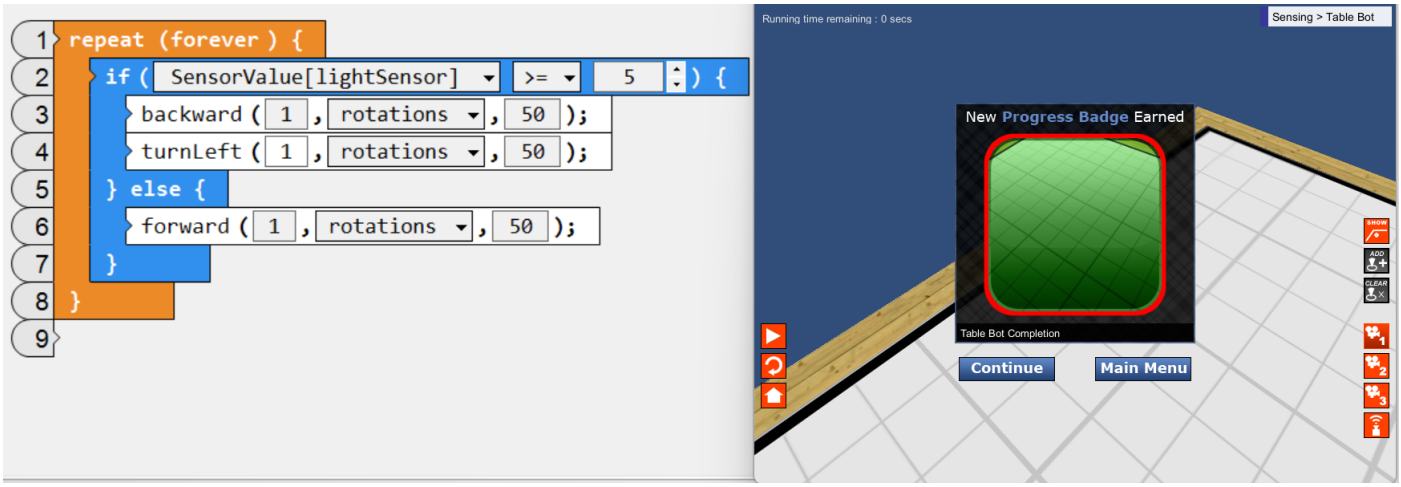
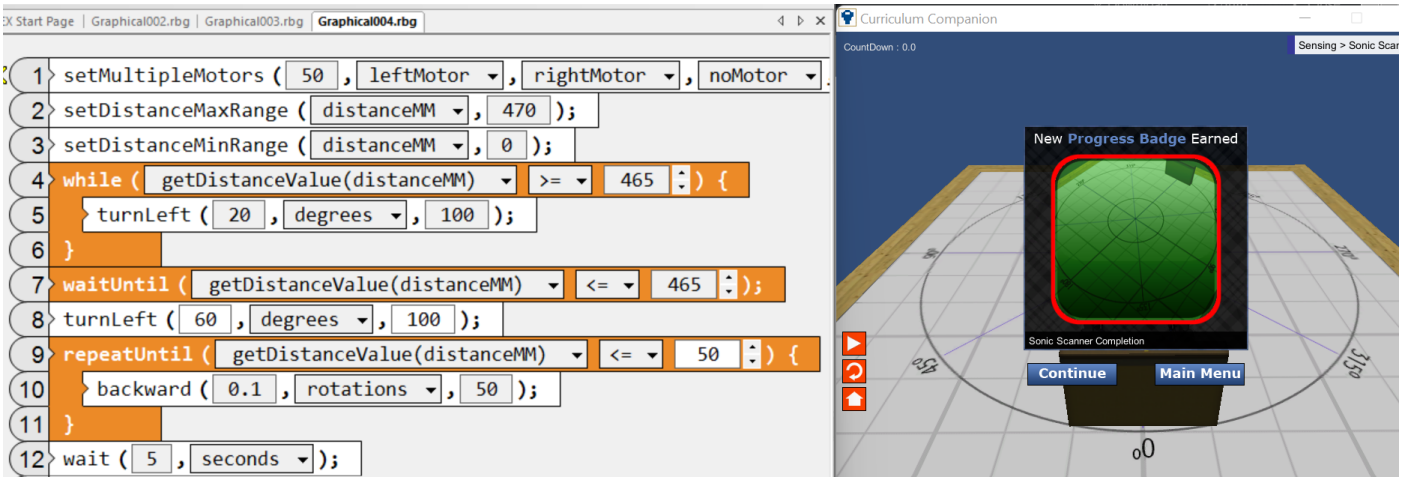

Debugger
Program
Robot
/EX Start Page | Graphical002.rbg | Graphical003.rbg | Graphical004.rbg | Graphical005.rbg | Graphical006.rbg
1 moveMotor (clawMotor , 2 , seconds , 50);
2 moveMotor (armMotor , 2 , seconds , 50);
3 forward (5 , seconds , 50);
4 moveMotor (armMotor , 2 , seconds , -50);
5 moveMotor (clawMotor , 2 , seconds , -50);
6 backward (5 , seconds , 50);
7
Challenge Pack
Basic Movement > Cargo Transport Challenge
New Progress Badge Earned
SPECIAL DELIVERY CHALLENGE
Special Delivery
Continue
Main Menu


repeat (forever) {
if (SensorValue[lightSensor] >= 5) {
backward (1 , rotations , 50);
turnLeft (1 , rotations , 50);
} else {
forward (1 , rotations , 50);
}
}
Running time remaining : 0 secs
Sensing > Table Bot
New Progress Badge Earned
Table Bot Completion
Continue
Main Menu

```
1  moveMotor ( armMotor , 1 , seconds , 50 );
2  forward ( 5.2 , seconds , 50 );
3  moveMotor ( clawMotor , 1 , seconds , 30 );
4  backward ( 2 , rotations , 50 );
5  turnRight ( 1 , rotations , 50 );
6  forward ( 1.5 , rotations , 50 );
7  turnLeft ( 1 , rotations , 50 );
8  forward ( 9.3 , rotations , 50 );
9  turnLeft ( 1 , rotations , 50 );
10 forward ( 1.4 , rotations , 50 );
11 turnRight ( 1 , rotations , 50 );
12 moveMotor ( clawMotor , 1 , rotations , -50 );
```


X Start Page | Graphical002.rbg | Graphical003.rbg | Graphical004.rbg
1 setMultipleMotors (50 , leftMotor , rightMotor , noMotor);
2 setDistanceMaxRange (distanceMM , 470);
3 setDistanceMinRange (distanceMM , 0);
4 while (getDistanceValue(distanceMM) >= 465) {
5 turnLeft (20 , degrees , 100);
6 }
7 waitUntil (getDistanceValue(distanceMM) <= 465);
8 turnLeft (60 , degrees , 100);
9 repeatUntil (getDistanceValue(distanceMM) <= 50) {
10 backward (0.1 , rotations , 50);
11 }
12 wait (5 , seconds);
Curriculum Companion
CountDown : 0.0
Sensing > Sonic Scar
New Progress Badge Earned
Sonic Scanner Completion
Continue
Main Menu
45
315
0