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# Project: VEXcode Project

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# Created:

# Description: VEXcode VR Python Project

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# Library imports

from vexcode import \*

brain.clear()

#function is running

def getLineBrightness(\*LineList):

global Csum,avg,Line,dec,i,p,c,i

avg=0

Csum=0

i=0

p=0

dec=0

c=1

line=0

i=0

while c<=5:

p=0

for Line in LineList:

brain.print(f"{LineList[i]}")

dec=dec+(LineList[line]\*pow(2,p))

p=p+1

line=line+1

i=i+1

if p==8:

brain.print(f"-->{dec}---")

i=line

break

pass

wait(5, MSEC)

brain.print(chr(dec))

brain.new\_line()

dec=0

c=c+1

wait(5, MSEC)

# Add project code in "main"

def main():

global control,j,Turn\_Control

j=0

Turn\_Control=1

drivetrain.set\_drive\_velocity(70, PERCENT)

monitor\_sensor("left\_bumper.pressed")

drivetrain.drive(FORWARD)

colors=[]

while j<=8:

#if bumper is 0,continue the loop

while not left\_bumper.pressed() :

control=1

while down\_eye.detect(BLUE):

if control!=0:

colors.append(0)

control=0

pass

wait(5,MSEC)

while down\_eye.detect(GREEN):

if control!=0:

colors.append(1)

control=0

pass

wait(5,MSEC)

wait(5, MSEC)

#if bumper is true and i variable is 8, break the loop.

if left\_bumper.pressed() and j==8:

break

pass

#program is controlling the direction of robot

if Turn\_Control==1:

drivetrain.turn\_for(RIGHT, 90, DEGREES)

drivetrain.drive\_for(FORWARD, 195, MM)#it can change becouse of internet connection

drivetrain.turn\_for(RIGHT,90,DEGREES)

drivetrain.drive(FORWARD)

Turn\_Control=0

pass

else:

drivetrain.turn\_for(LEFT, 90, DEGREES)

drivetrain.drive\_for(FORWARD, 195, MM)#it can change becouse of internet connection

drivetrain.turn\_for(LEFT,90,DEGREES)

drivetrain.drive(FORWARD)

Turn\_Control=1

pass

j=j+1

wait(5, MSEC)

#run the function

getLineBrightness(\*colors)

brain.new\_line()

#write the colors list to consol

brain.print(colors)

brain.new\_line()

drivetrain.stop()

stop\_project()

# VR threads — Do not delete

vr\_thread(main())