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Robotc 4 X Keygen Crack

| C ROBOTC  |  |   |   |   |  |
|---|--|---|---|---|--|
| File Edit View Robot Window Help                            |  |   |   |   |  |
| New File Open File Save                                     |  | Compile<br>Program Download to<br>Robot | Start Stop  |   |  |
| Fext Functions 🔍 🔻 🗶  | Detect Color   | r - 12 Color Mode Advanced.c            |   | 4 Þ   |  |
| · ~Control Structures                                       | 1  | <pre>#pragma config(Sensor, p</pre>     | ort3, colorDetector, sensorVexIQ_Color12Color)  |   |  |
| 📄 Math  | 2  | <pre>//*!!Code automatically</pre>      | generated by 'ROBOTC' configuration wizard  | !!*//   |  |
| Commands  | 3  |   |   |   |  |
| 😑 Variables   | 4  | /*                                      |   |   |  |
| PI  | 5  |   | the VEX IQ Color sensor in "12 Color" mode. This mode   | -   |  |
| rand()  | 6  | color values as oppose                  | d to a "Hue" value. This is helpful for detecting speci   | fic colors.                                   |  |
| random[]  | 7  |   |   |   |  |
| - Motors  | 8  | The 12 valid color nam                  |   |   |  |
| - Commands  | 9  |   |   |   |  |
| getMotorCurrent(nMotorIndex);                               | 10   |   | Green / colorBlueGreen / colorBlue / colorDarkBlue / co   |   |  |
| getMotorEncoder(nMotorIndex);                               | 11   |   |   | */  |  |
| moveMotorTarget(nMotorIndex, nPosition, nSpe                | 12   | task main()                             |   |   |  |
| resetMotorEncoder(nMotorIndex);                             | 13   | (                                       |   |   |  |
| setMotorReversed(nMotorIndex, bReversed);                   | 14   | while(true)                             |   |   |  |
| setMotorSpeed(nMotorIndex, nSpeed);                         | 15   | {                                       |   |   |  |
| setMotorTarget(nMotorIndex, nPosition, nSpeed               | 16 //The switch command tells us which value we want to check against. 17 switch (getColorName(colorDetector)) |   |   |   |  |
| ··· Variables   | 18   | switch (getColorName (                  | colorDetector))   |   |  |
| Sensors   | 18   | 1<br>(/=                                |   |   |  |
| · Variables   | 20   |   | he color we want to check for. Once we find a color, we<br>end with a "break" command to say we're done in the "s |   |  |
| Bumper Sensor   | 20   | case colorRedViole                      |   | witch" and continue on with the program.      |  |
| getBumperValue(nDeviceIndex);                               | 21   | case colorredviole                      |   |   |  |
|   | 22   | i<br>di milan Manti ina (               | 1, "Color: Red Violet");  |   |  |
| Color Sensor  | 23   | break:                                  | i, "Color: Red Violet");  |   |  |
| — getColorGrayscale(nDeviceIndex);                          | 25   | DI Cak,                                 |   |   |  |
| getColorHue(nDeviceIndex);                                  | 26   | case colorRed;                          |   |   |  |
| getColorName(nDeviceIndex);                                 | 27   | /                                       |   |   |  |
| getColorValue(nDeviceIndex);                                | 28   | dienlawTextline(                        | 1, "Color: Red");   |   |  |
| TouchLED Sensor   | 29   | break;                                  | i, color. Red /,  |   |  |
| — getTouchLEDValue(nDeviceIndex);                           | 30   | )                                       |   |   |  |
| <ul> <li>setTouchLEDColor(nDeviceIndex, nColor);</li> </ul> | 31   | //Case statements                       | can also be written without curly brackets to save time   |   |  |
| — setTouchLEDHue(nDeviceIndex, nHueValue);                  | 32   |   | ntinue running code until it sees a "break".  |   |  |
| setTouchLEDRGB(nDeviceIndex, red, green, blue               | 33   |   | <pre>ge: displayTextLine(1, "Color: Dark Orange"); break;</pre>   |   |  |
| Distance Sensor   | 34   | case colorOrange:                       | displayTextLine(1, "Color: Orange"); break;   |   |  |
| getDistanceValue(nDeviceIndex);                             | 35   |   | ow: displayTextLine(1, "Color: Dark Yellow"); break;  |   |  |
| setDistanceMaxRange(nDeviceIndex, nMaxDistar                | 36   | case colorYellow:                       | displayTextLine(1, "Color: Yellow"); break;   |   |  |
| setDistanceMinRange(nDeviceIndex, nMinDistan                | 37   |   | n: displayTextLine(1, "Color: Lime Green"); break;  |   |  |
| - Gyro Sensor   | 38   | case colorGreen:                        | <pre>displayTextLine(1, "Color: Green"); break;</pre>   | Program Debug                                 |  |
| Sound   |  |   |   |   |  |
| - Sounds  |  |   |   | Debug Status Refresh                          |  |
| Timing  | Index  | Sensor                                  | Type Value  |   |  |
| - Commands  |  |   | Touch LED 0   | Stop Suspend Step Continuous                  |  |
| - Variables   | port2<br>port3   | colorDetector                           | Touch LED 0<br>Color - Color Name 7   |   |  |
| VEX Remote Control  | port3<br>port4   | CONTRACTOR                              | Gyro Sensor -22   | Clear All Show PC                             |  |
| - Variables   | port4<br>port7   |   | Gyro Sensor -22<br>Distance (Sonar) 156   |   |  |
| T. Valiabies  | port /<br>port8  |   | Bumper (Touch) 1  |   |  |
| <b>&gt;</b>   | polto  |   | bumper (Touch)  |   |  |
| r Help, press F1  |  |   | Robot VEX-IO COM9 Detect Color - 12 Color   | Mode Advan R/O No compile errors Ln 46. Col 2 |  |

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