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6

Robotc 4 X Keygen Crack

C ROBOTC					
File Edit View Robot Window Help					
New File Open File Save		Compile Program Download to 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 (/=			
· Variables	20		he color we want to check for. Once we find a color, we 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 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 port3	colorDetector	Touch LED 0 Color - Color Name 7		
VEX Remote Control	port3 port4	CONTRACTOR	Gyro Sensor -22	Clear All Show PC	
- Variables	port4 port7		Gyro Sensor -22 Distance (Sonar) 156		
T. Valiabies	port / 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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