

# tinyBotSetDown

mimicBlock tinyBotSetDown.abp

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Control Pins Tests Math Operators Variables/Constants Generic Hardware Communication mimicRobots InputBox Racer

```
setup
loop
  Robot Move channel 2 position 127
  Robot Move channel 3 position 127
  delay MILLIS milliseconds 5000
  Robot Grab force 100
  delay MILLIS milliseconds 2000
  Robot Move channel 2 position 75
  You need to find the right position for Channel 3
  Experement with different numbers to find the one that
  sets the block down smoothly
  Robot Move channel 3 position 000
  Your number goes here ^^^
  Robot Grab force -100
  delay MILLIS milliseconds 1000
  Robot Grab force 0
program
```

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tinyBotSetDown | Arduino 1.8.11

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```
1 #include <robot.h>
2
3 void setup() {
4   // put your setup code here, to run once:
5   robotActivate();
6
7 }
8
9 void loop() {
10  // put your main code here, to run repeatedly
11  //Move robot to HOME position
12  robotMove(2,127);
13  robotMove(3,127);
14  delay(5000); //this command waits for 5000 milliseconds, which is the same as 5 seconds.
15  robotGrab(100); //The higher the number, the harder the robot grabs. 127 is the maximum
16  delay(2000); //let's wait 2000 milliseconds (2 seconds) to make sure the robot has a good grip
17  robotMove(2,75);
18
19  //This next step is incomplete. You need to add your channel three position
20  robotMove(3,???) ; //<--- PUT YOUR CHANNEL 3 POSITION HERE|
21  //Good job!
22
23  robotGrab(-100); //the negative number will open the gripper
24  delay(1000);
25  robotGrab(0); //we need to turn off the gripper by resting to zero. That keeps it from wearing out.
26
27
28 }
```

expected primary-expression before '?' token

expected primary-expression before '?' token