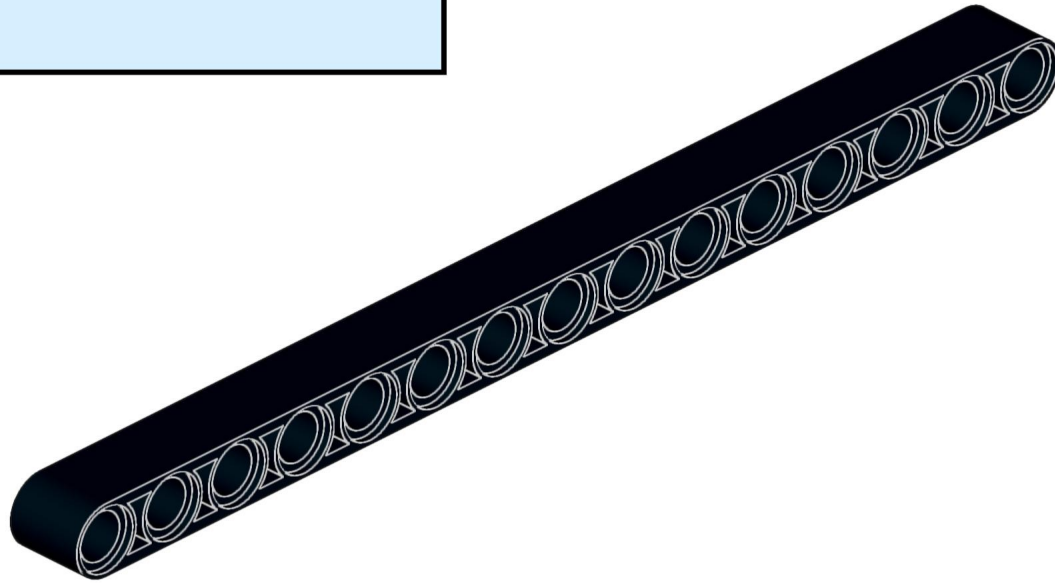
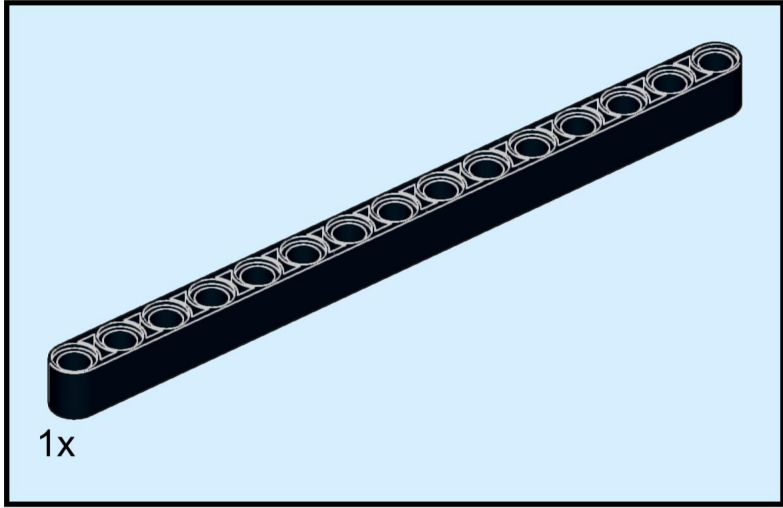
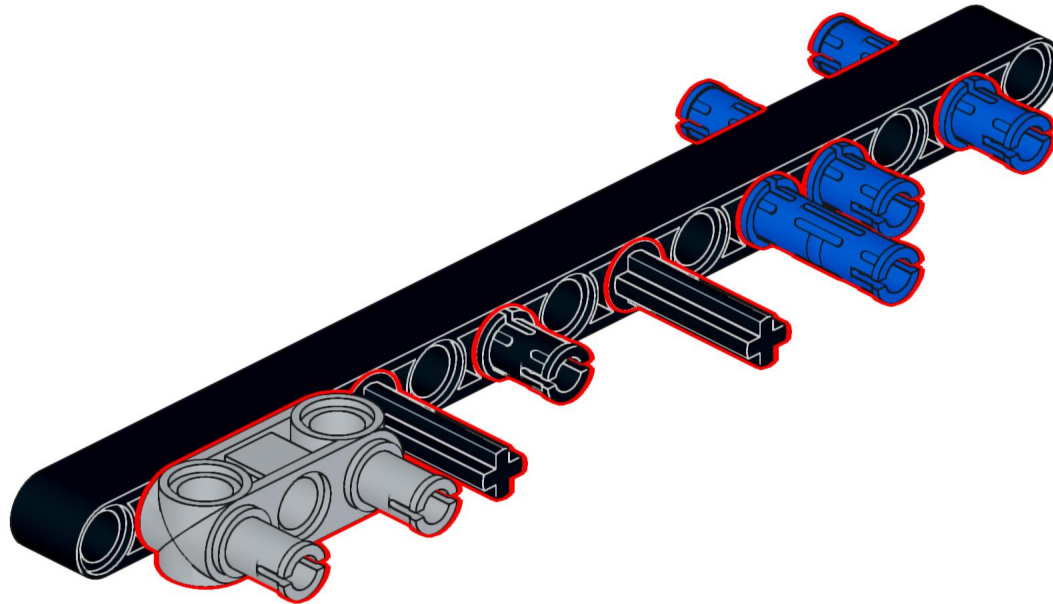
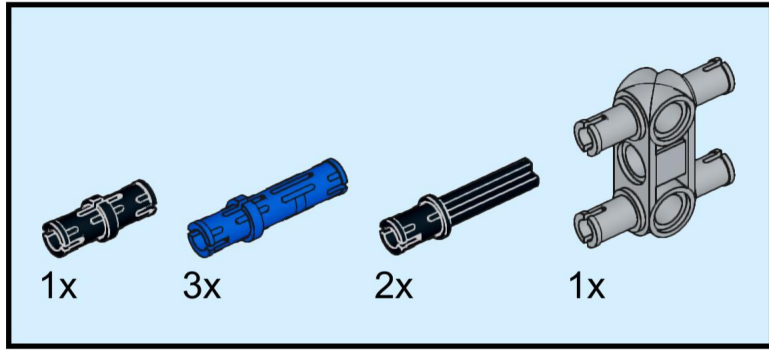


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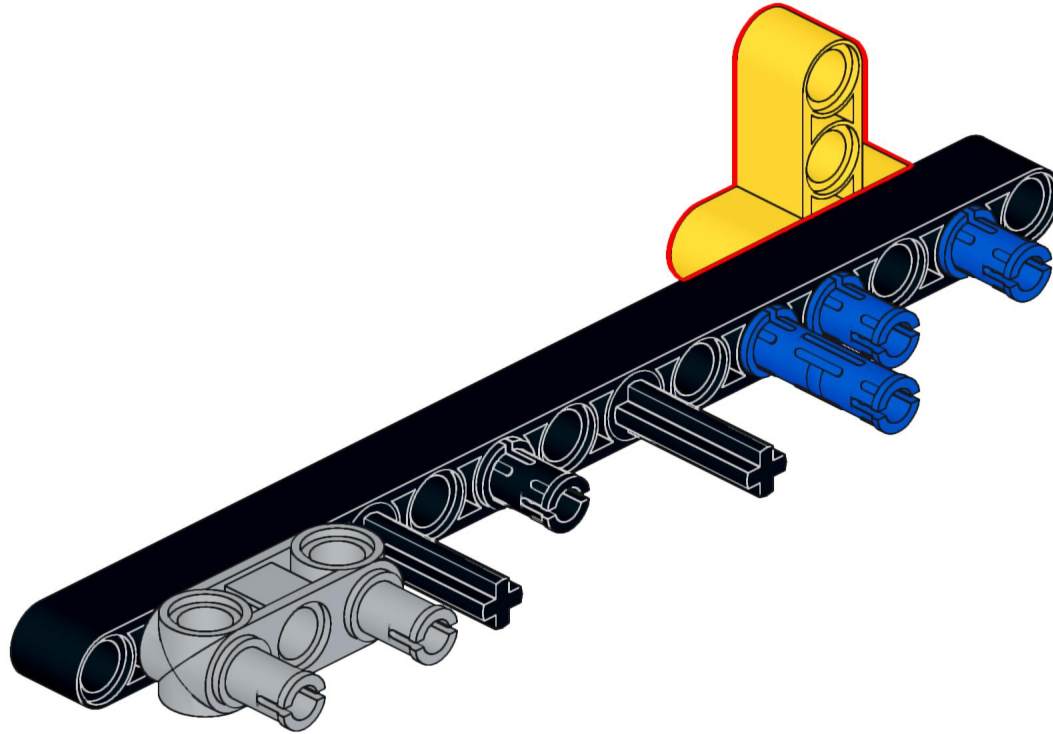
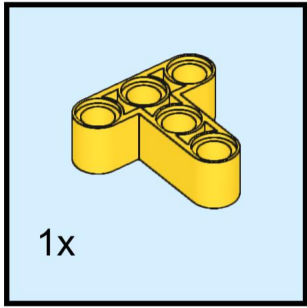
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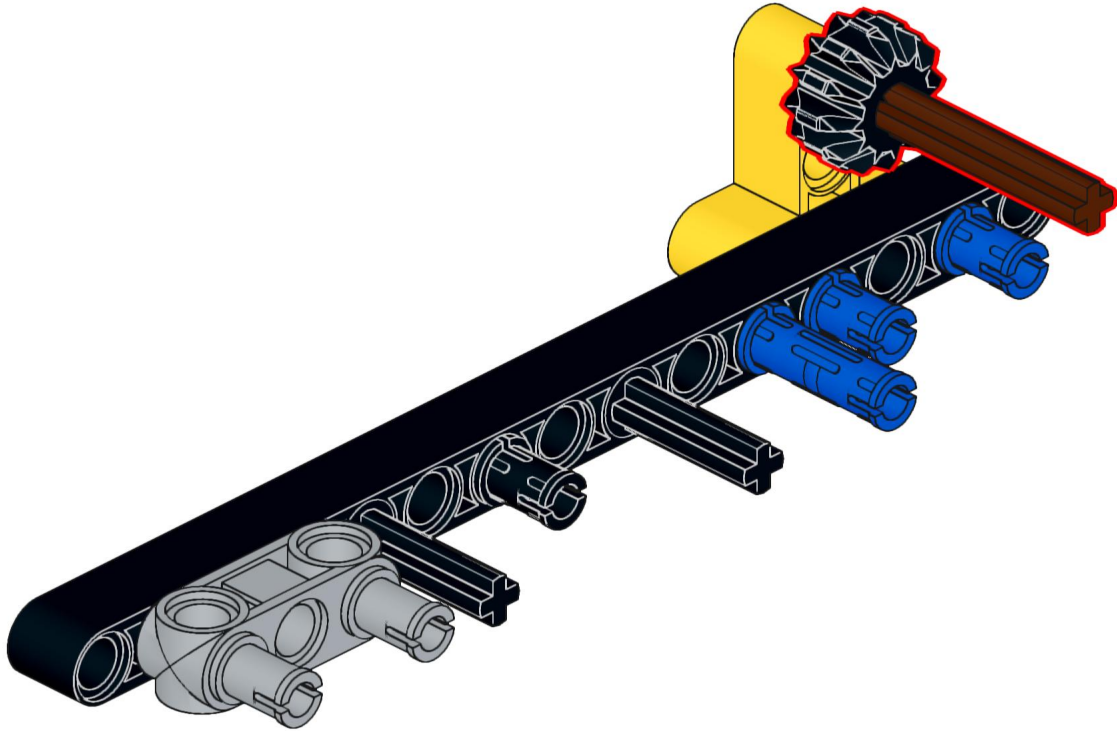
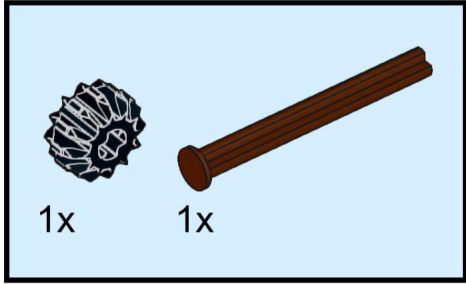
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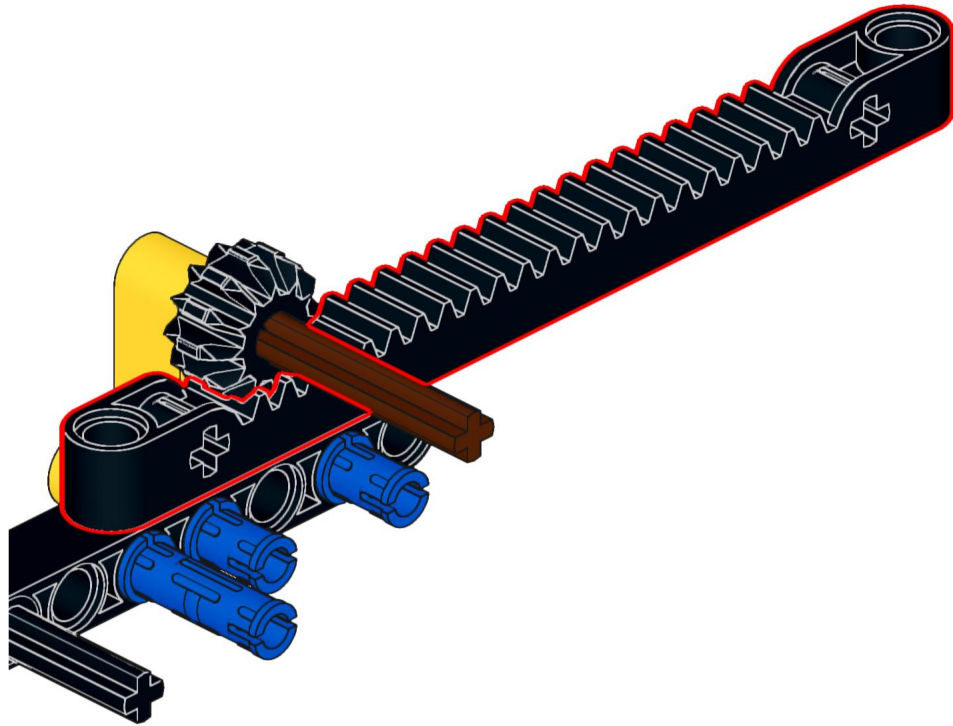
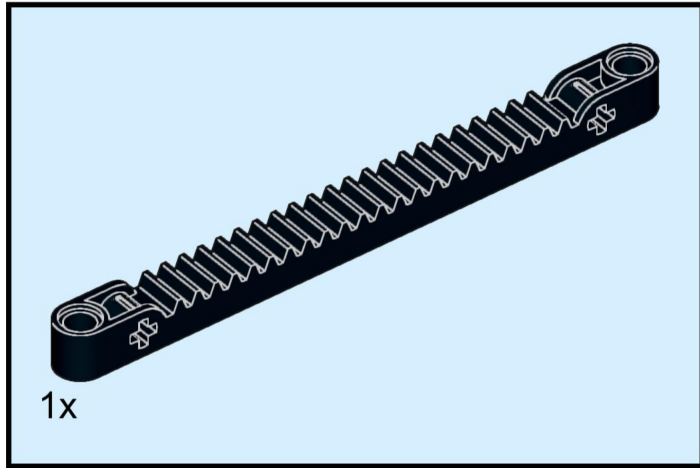
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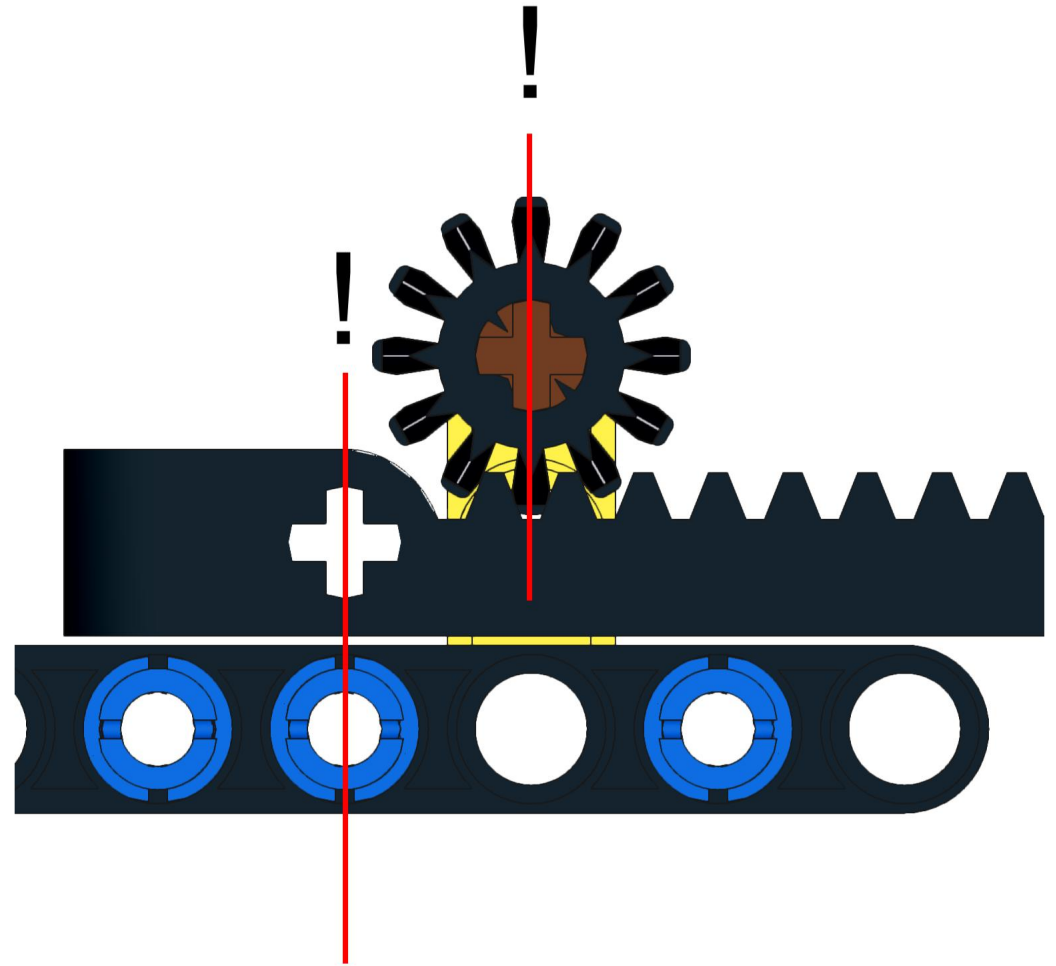
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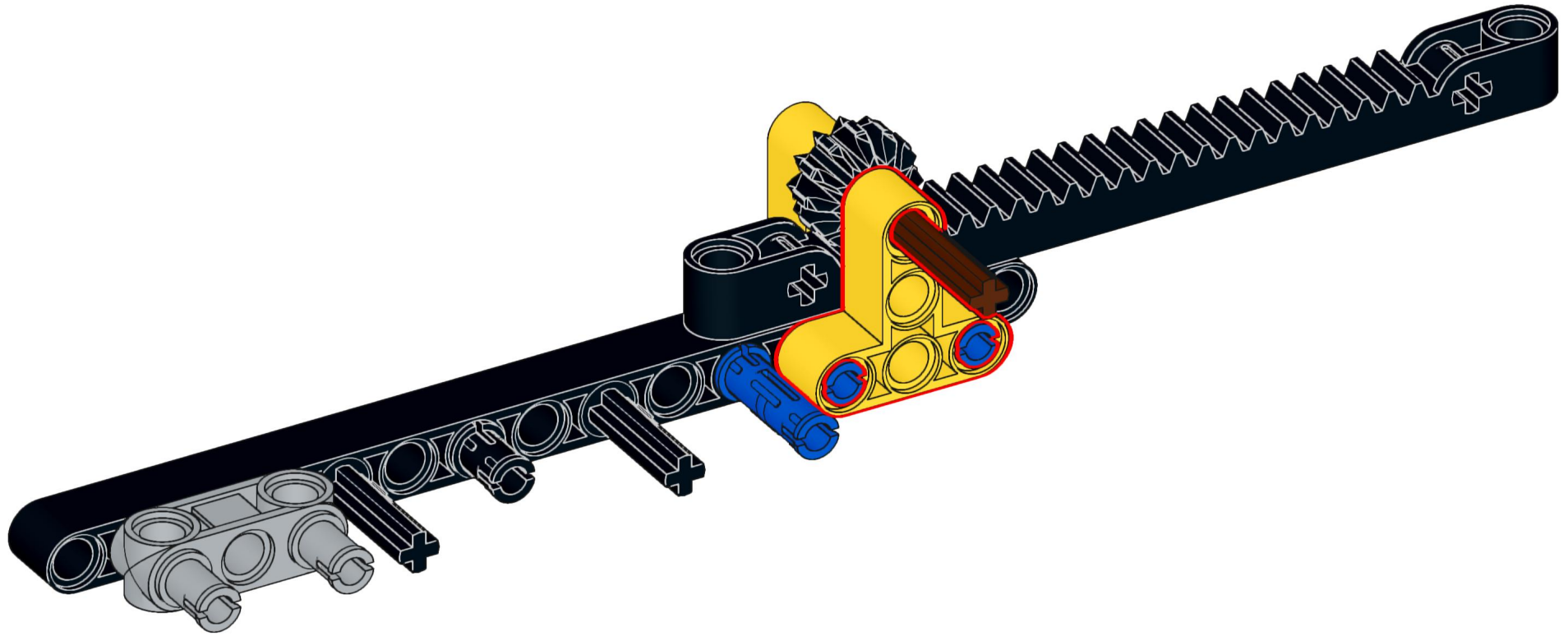
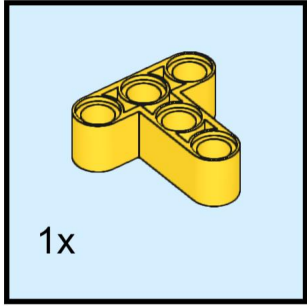
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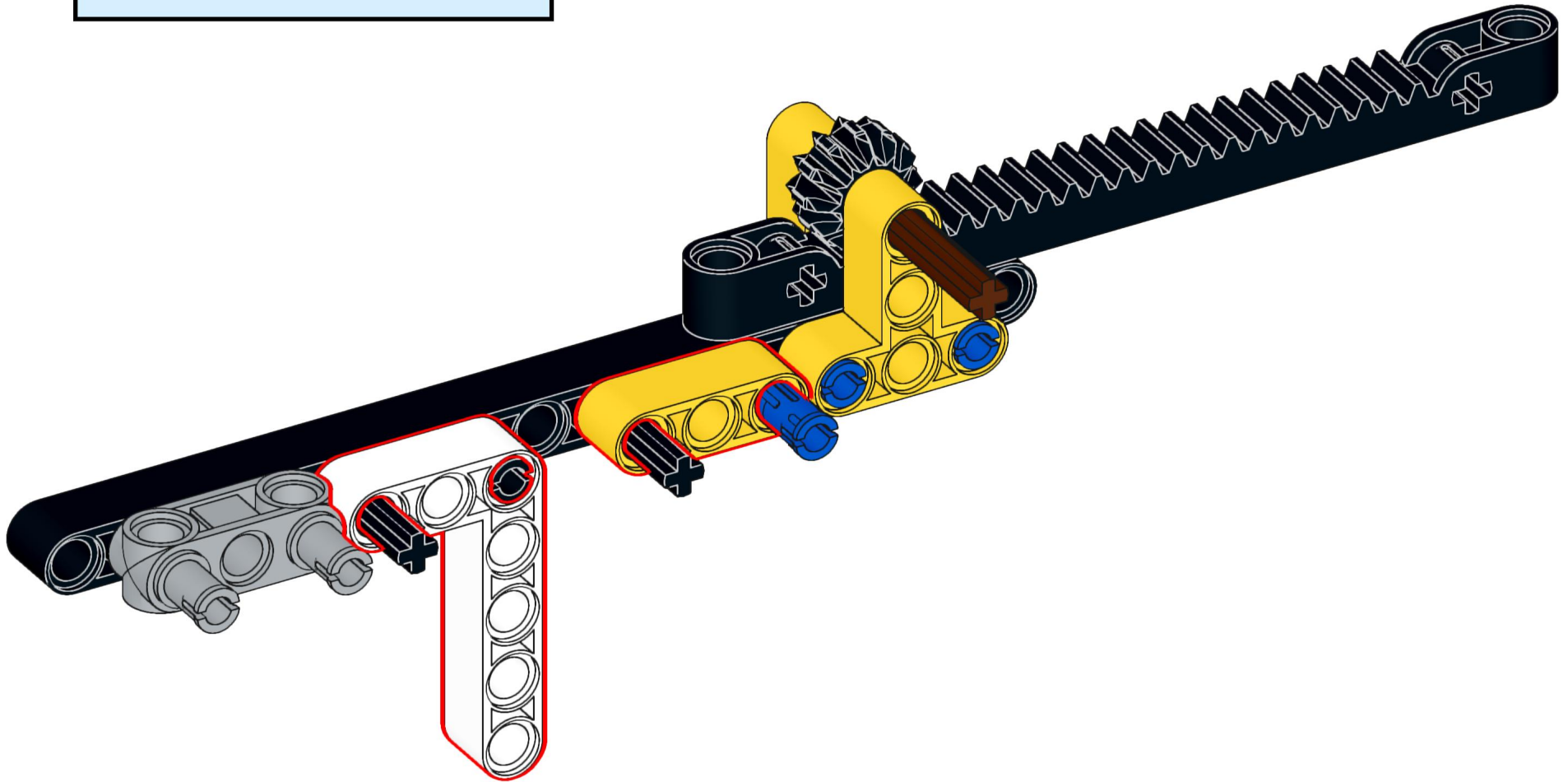
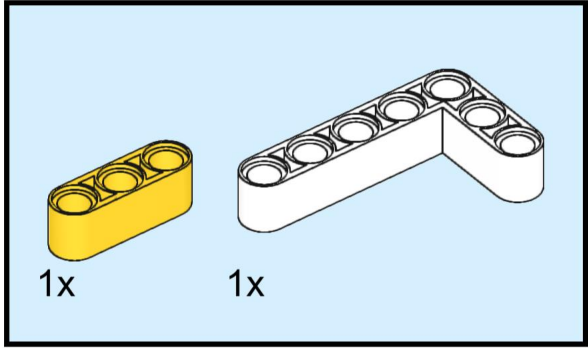
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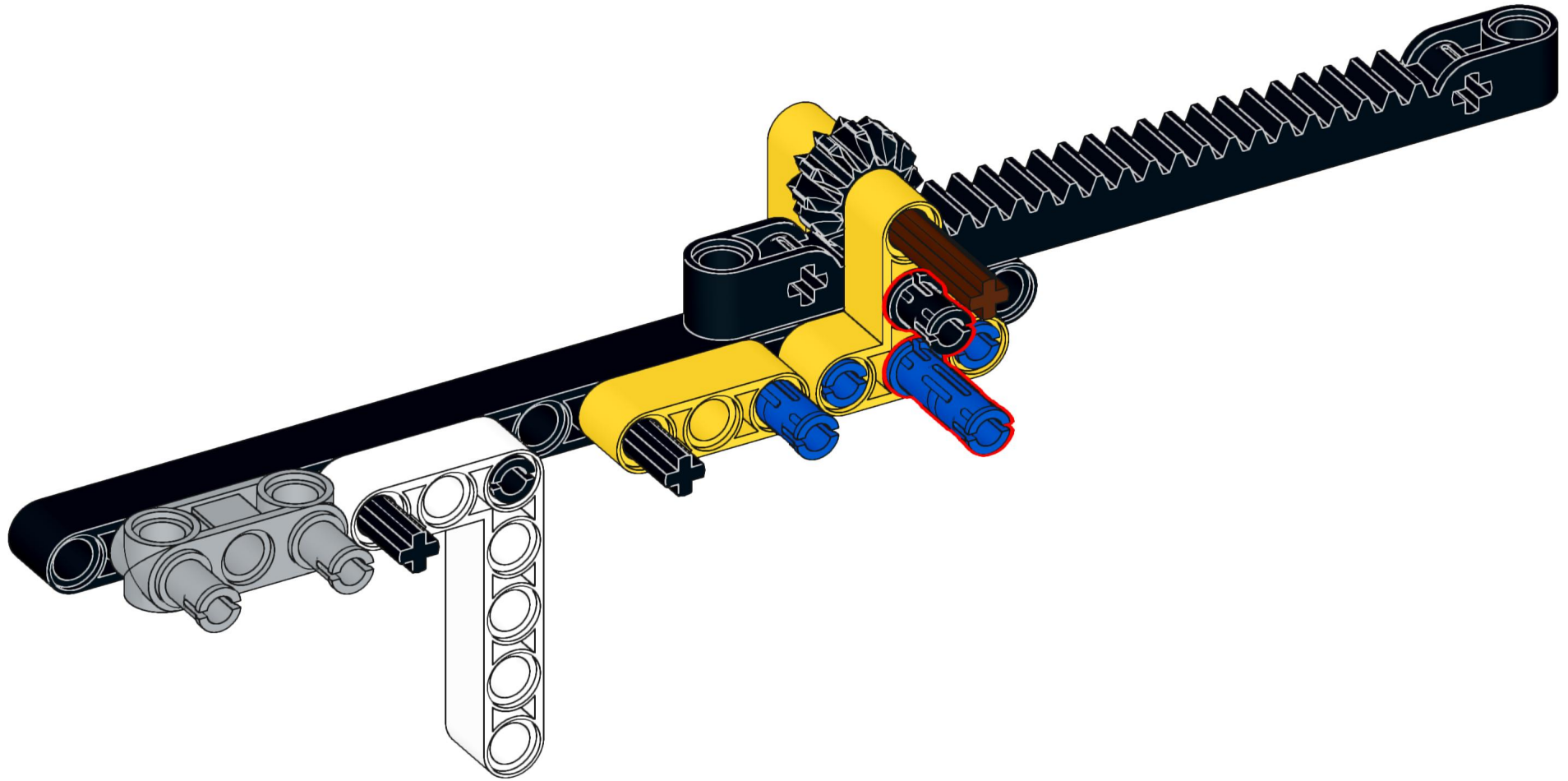
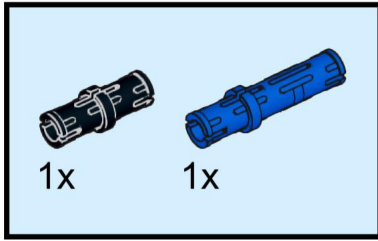
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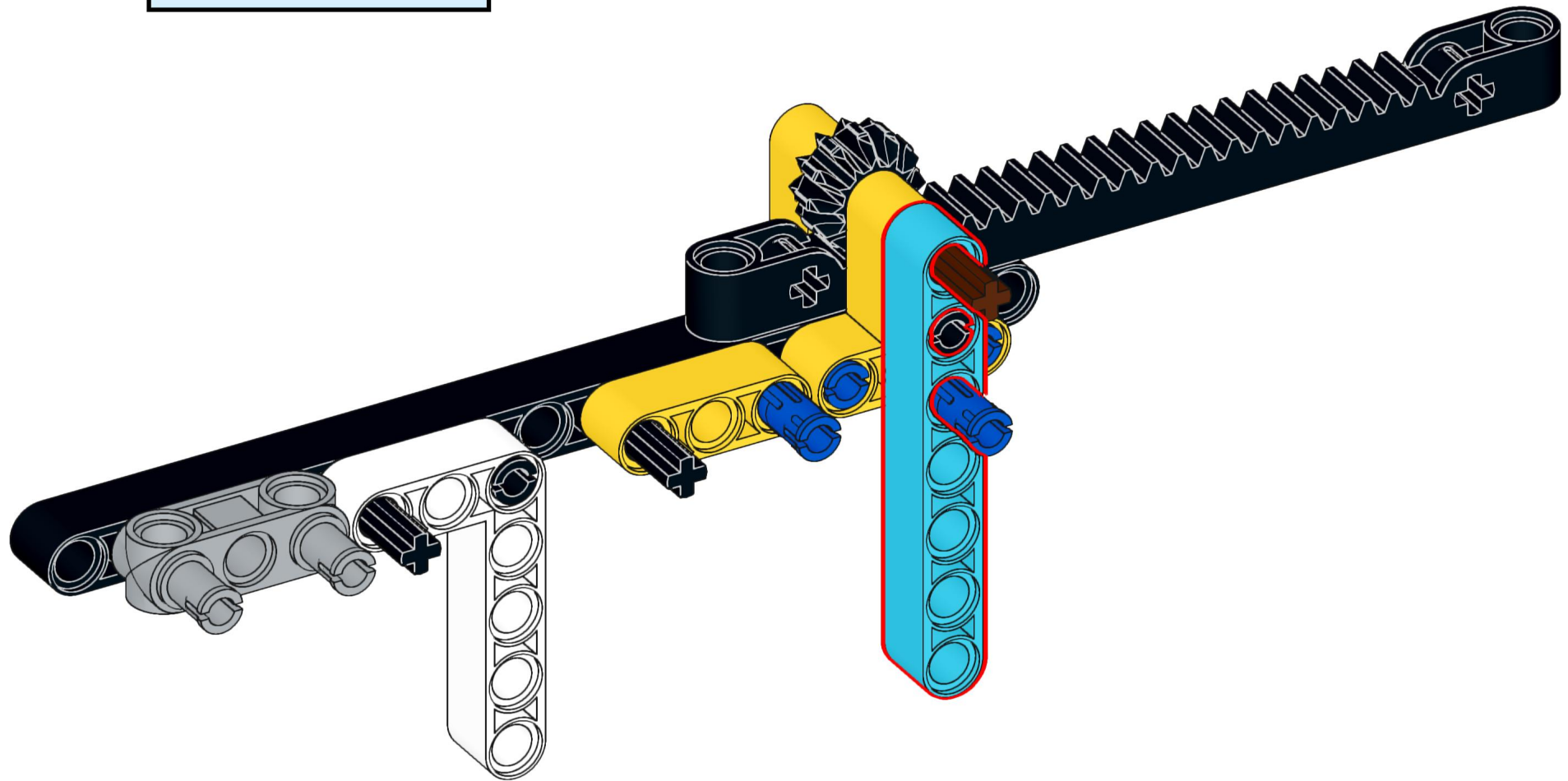
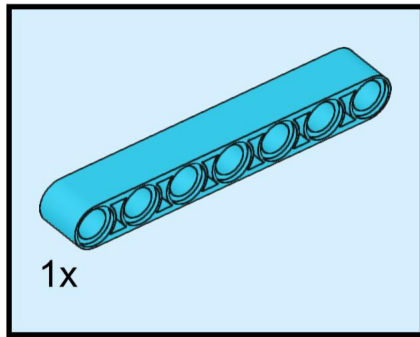
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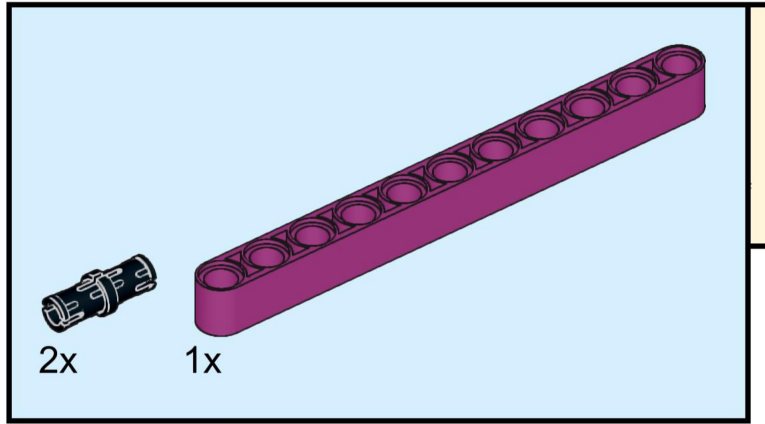
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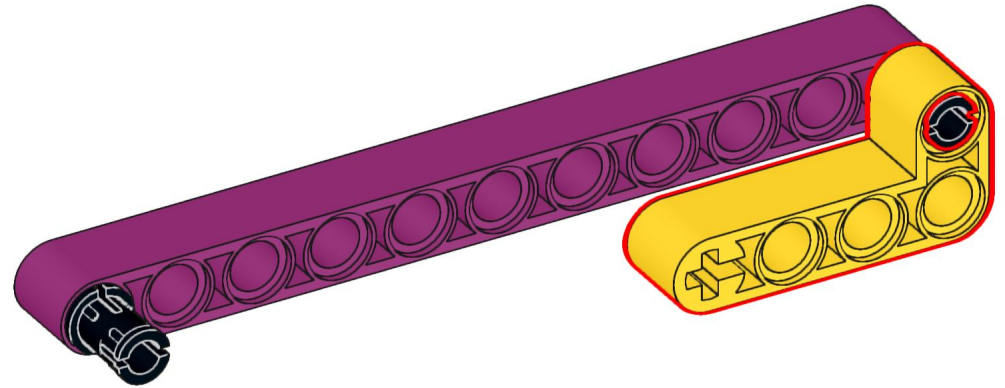
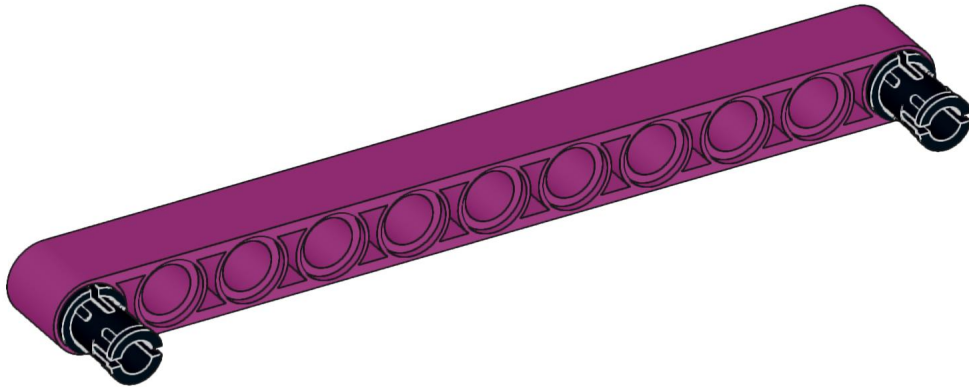
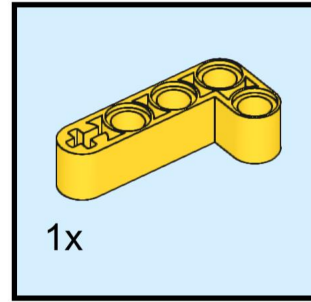
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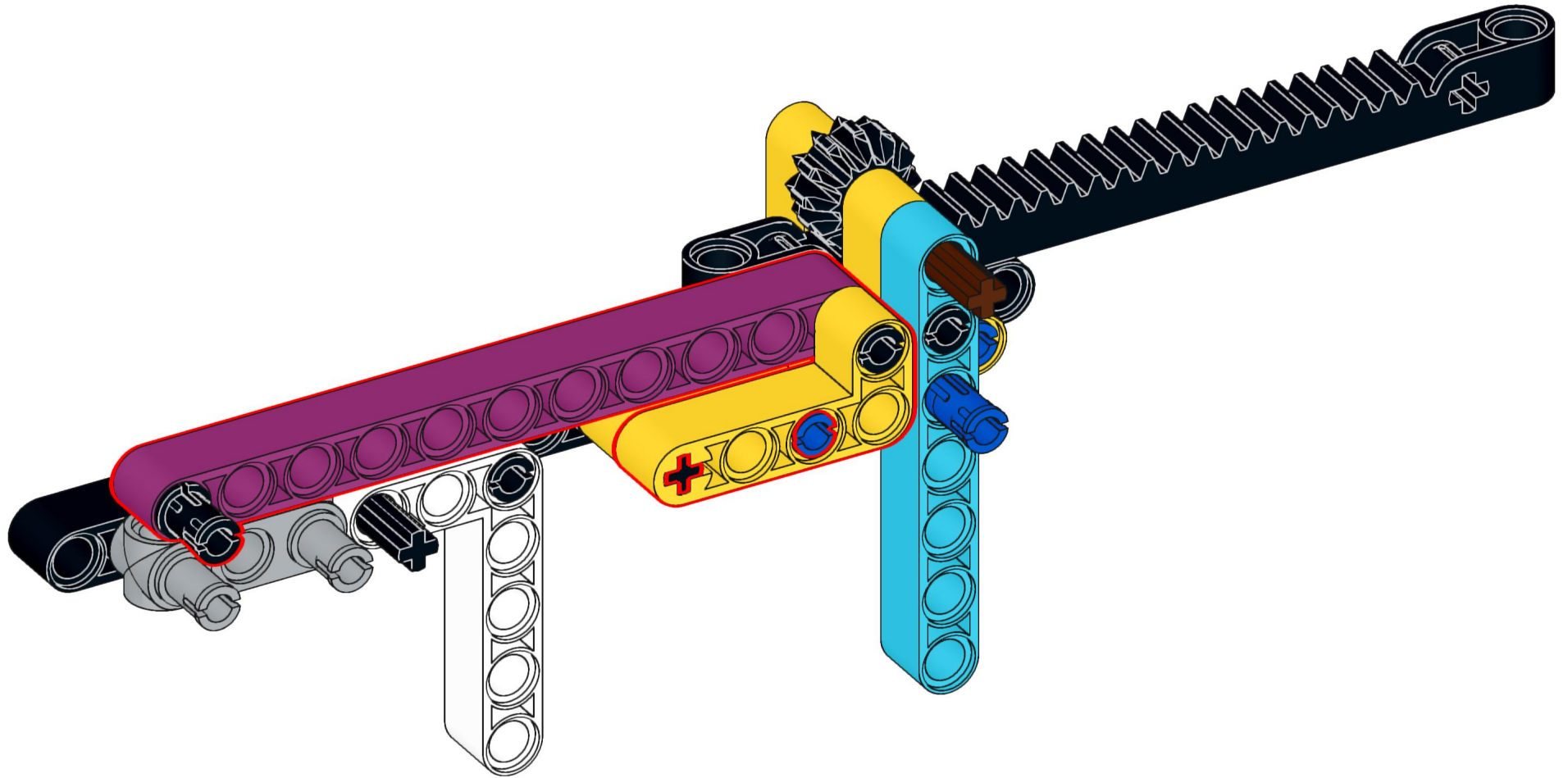
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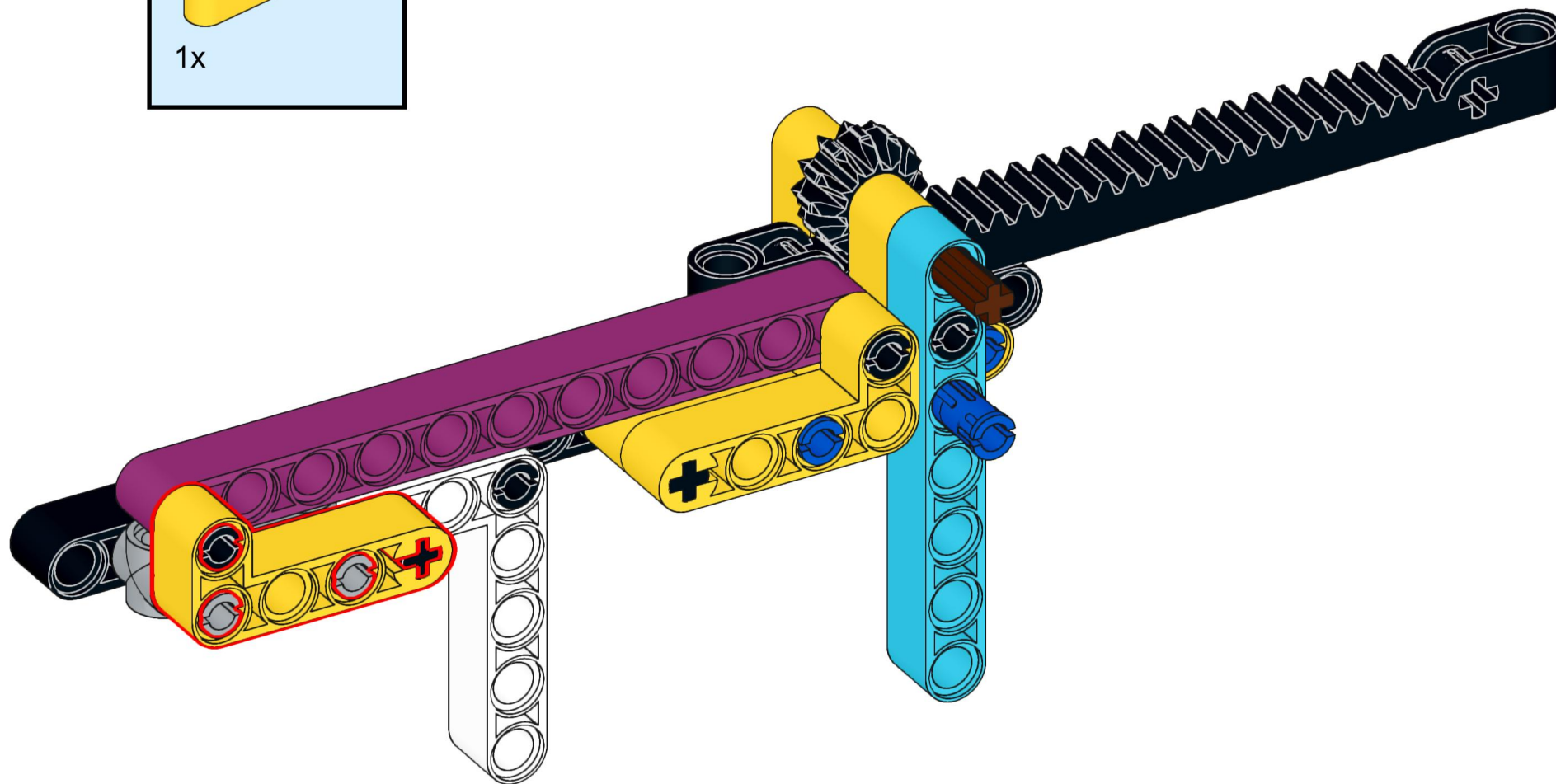
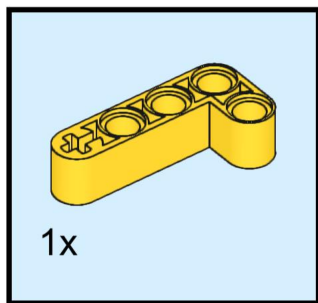
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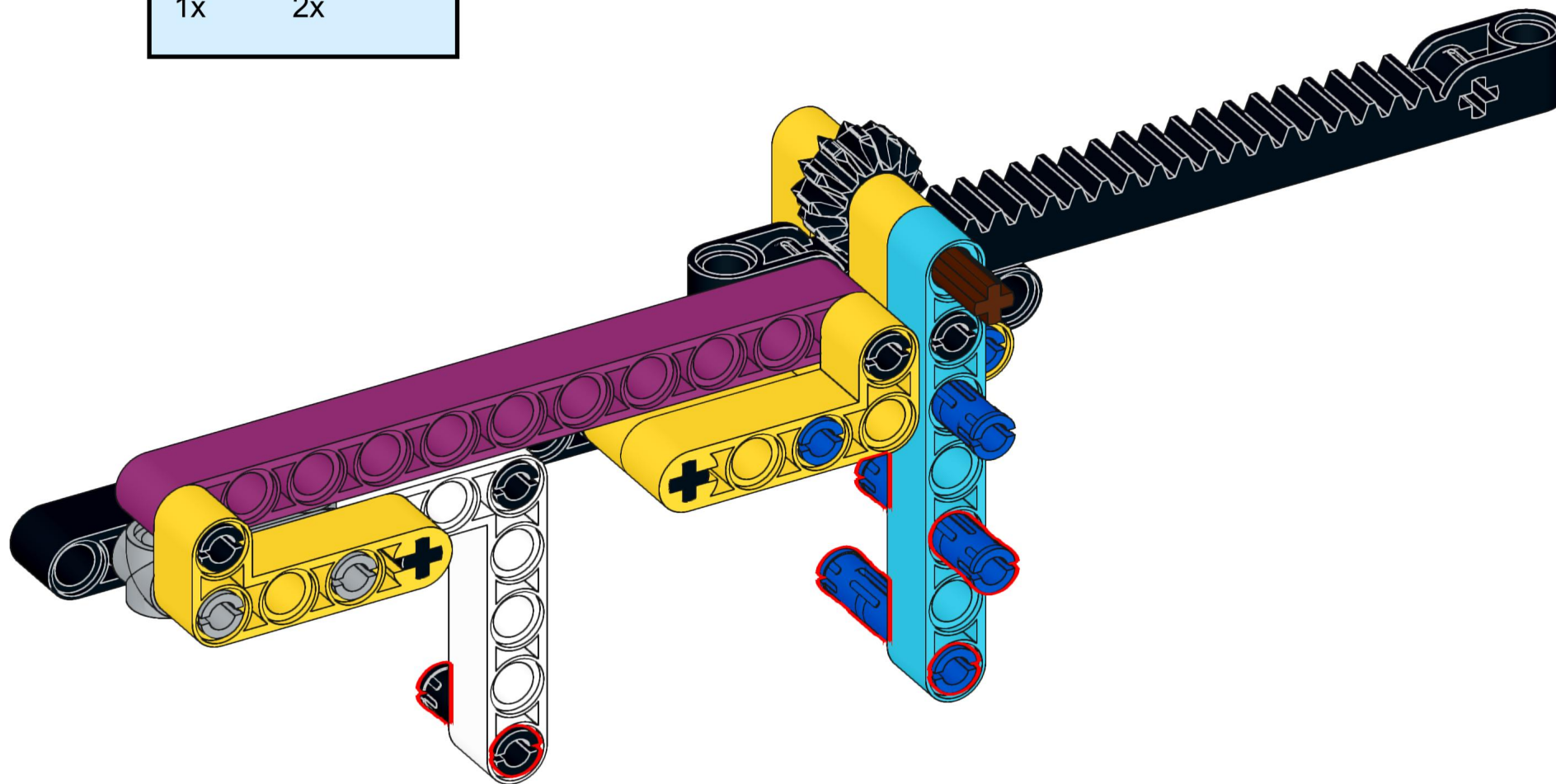
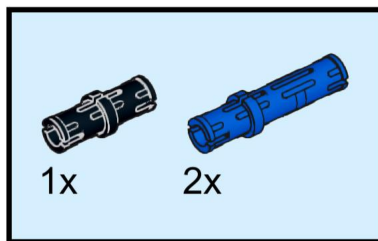
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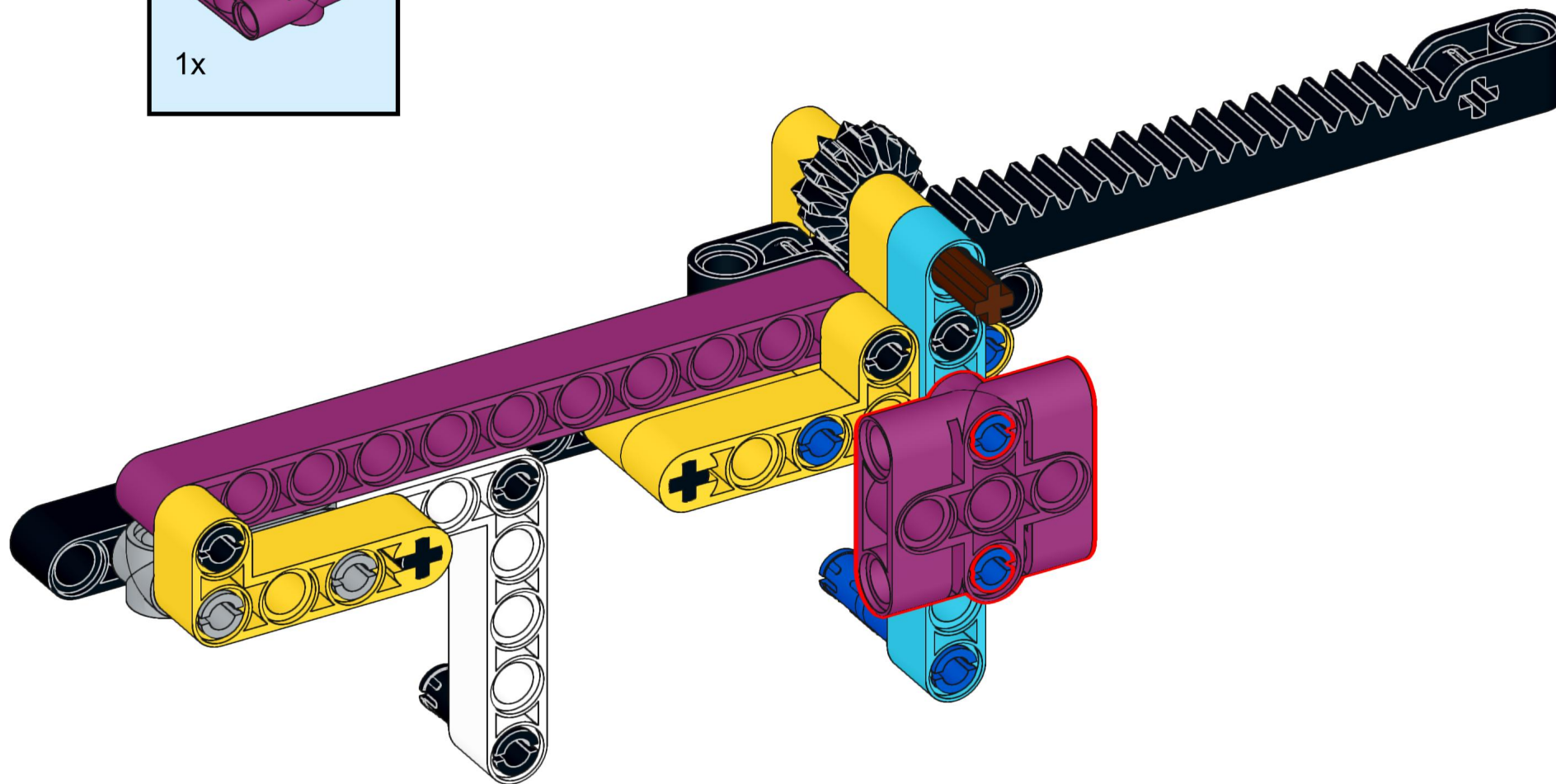
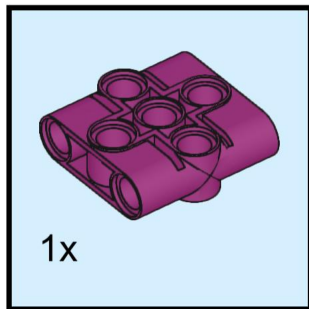
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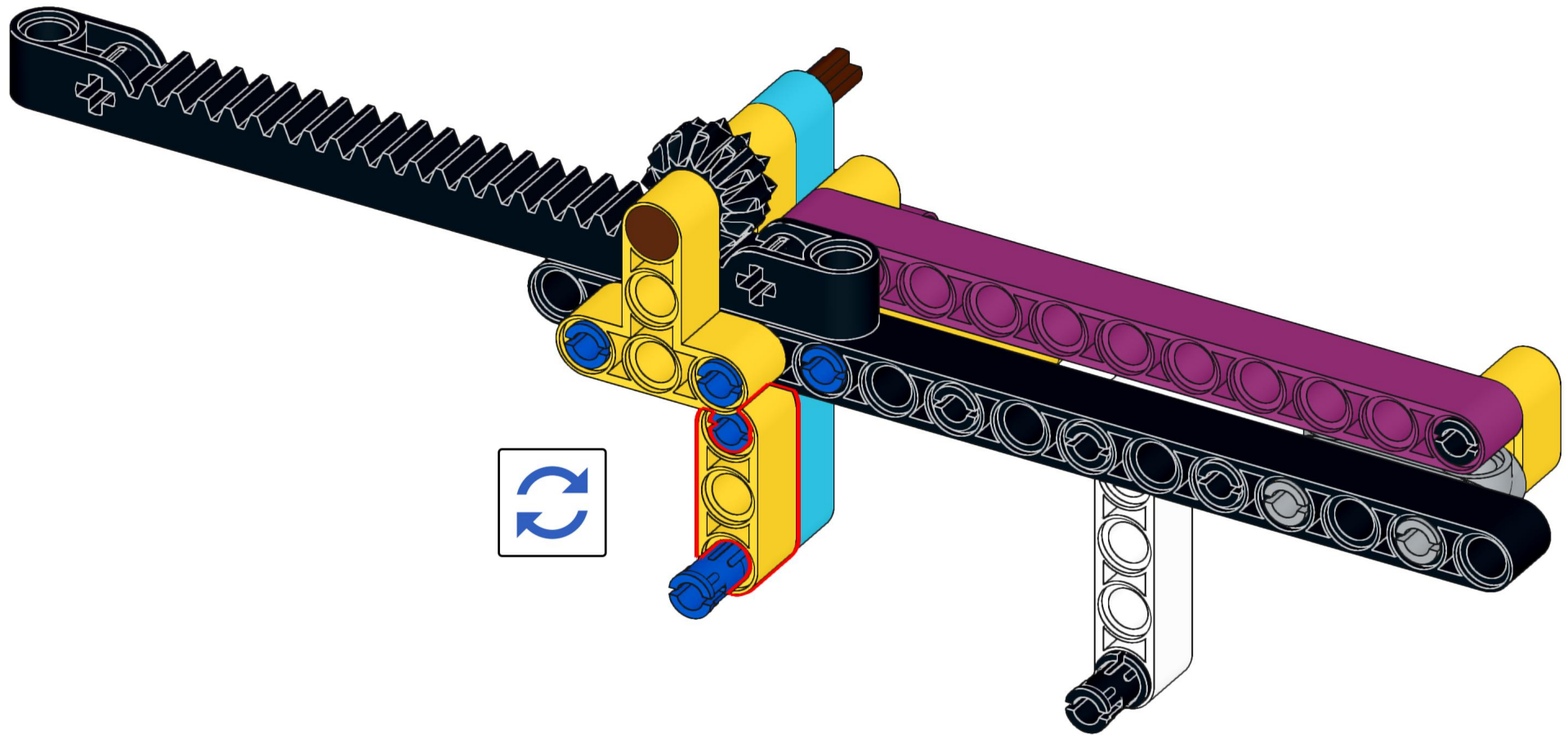
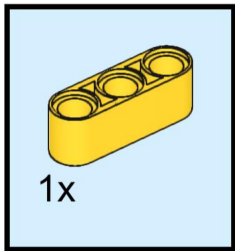
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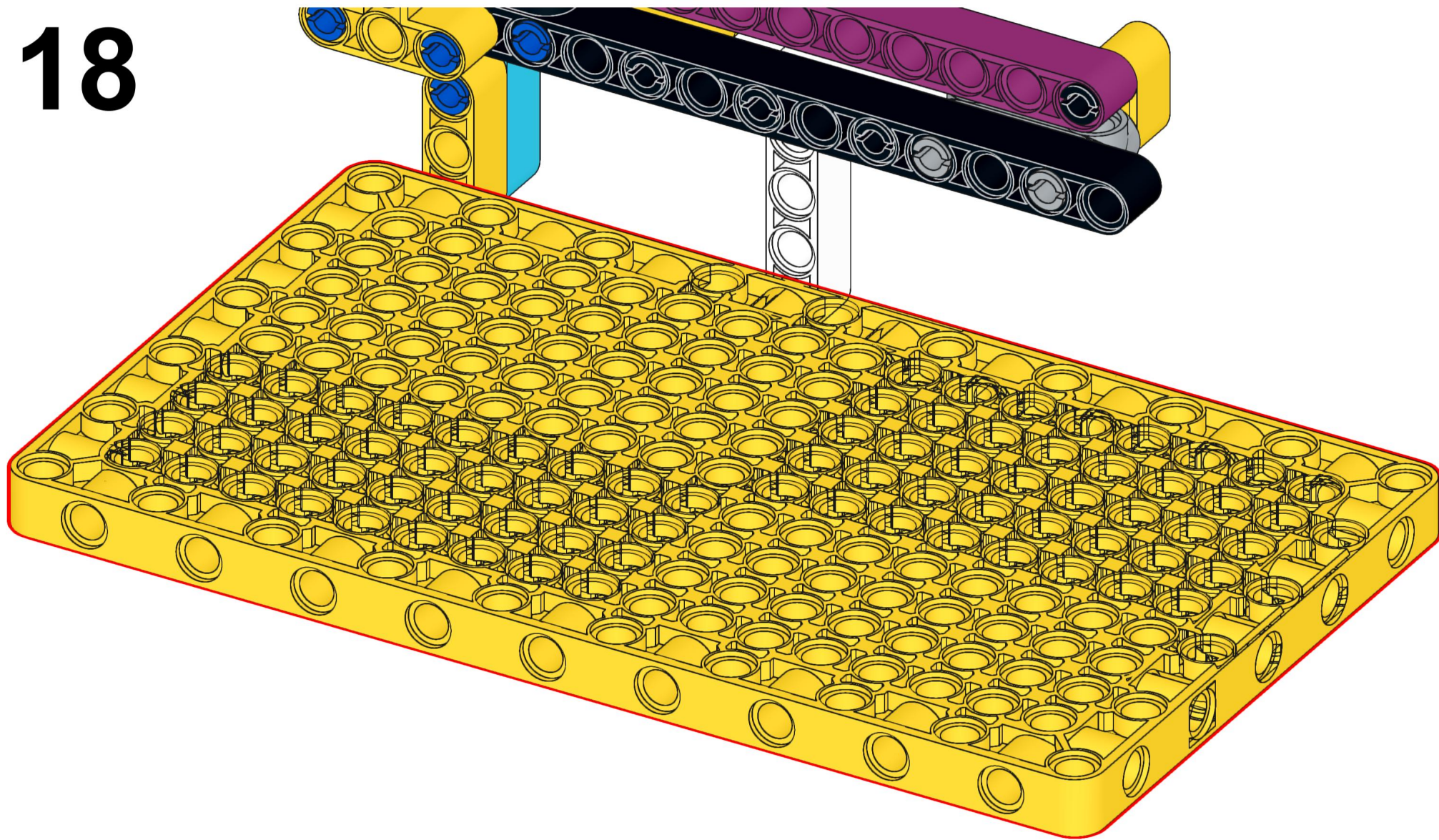
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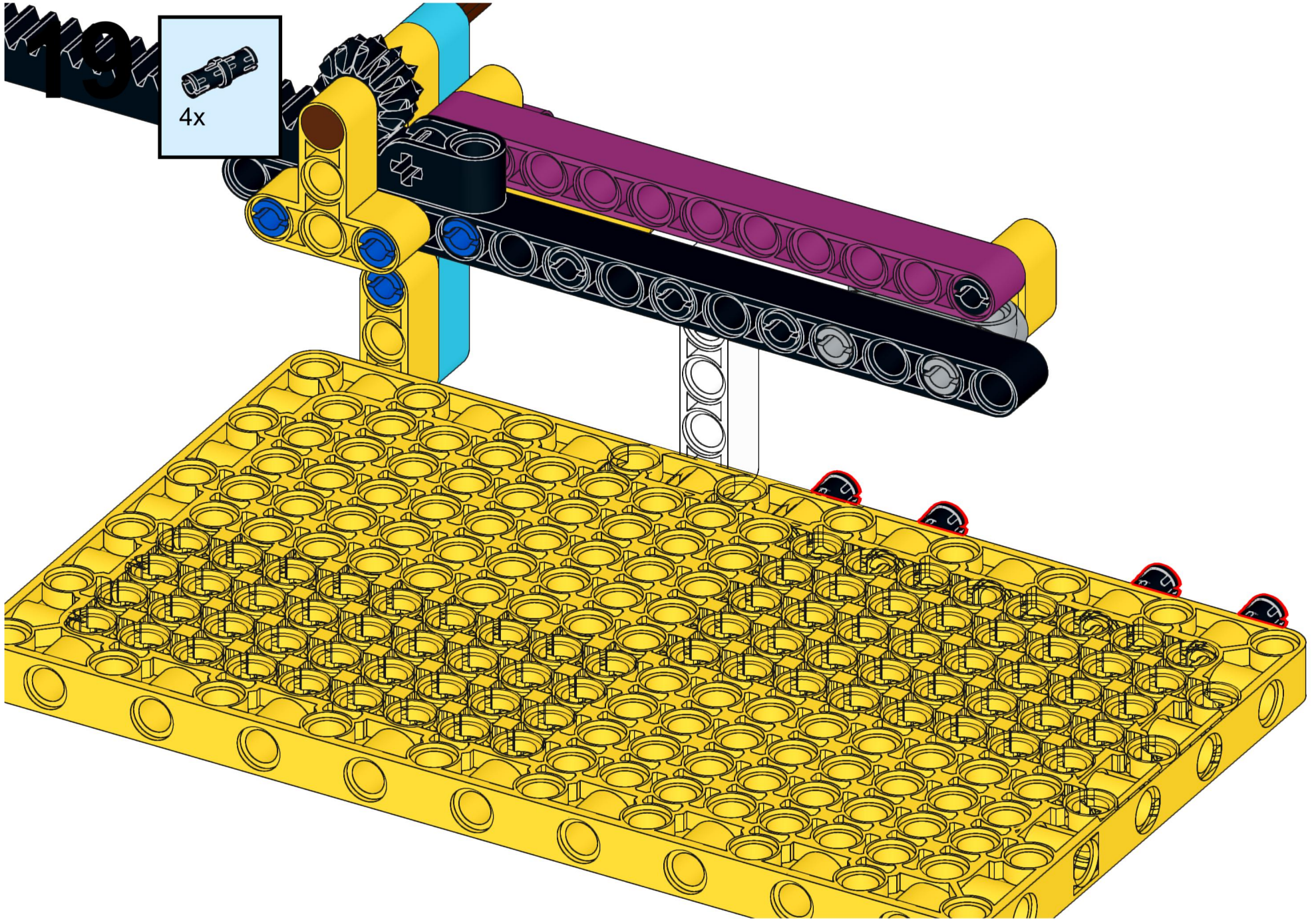


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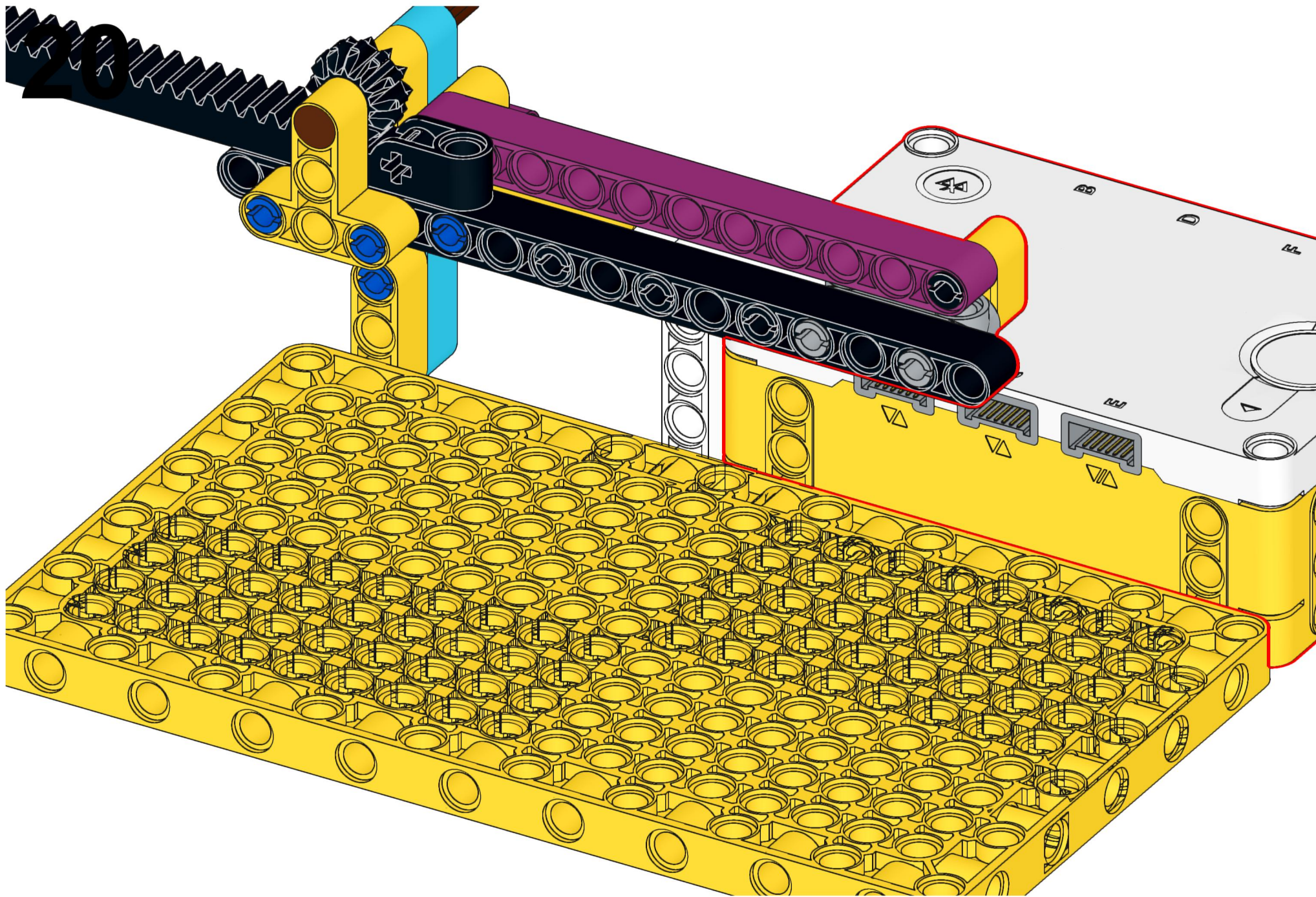


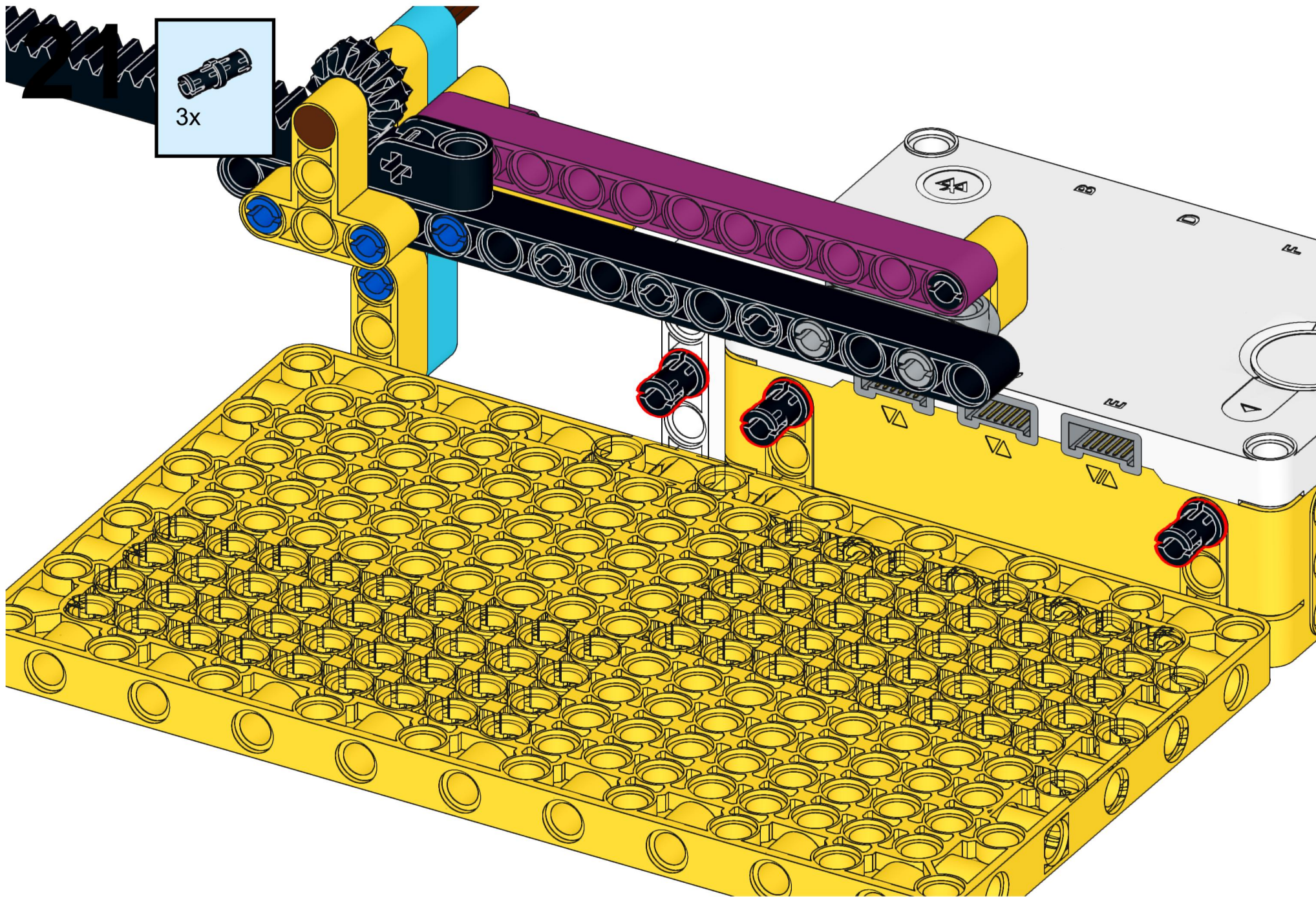
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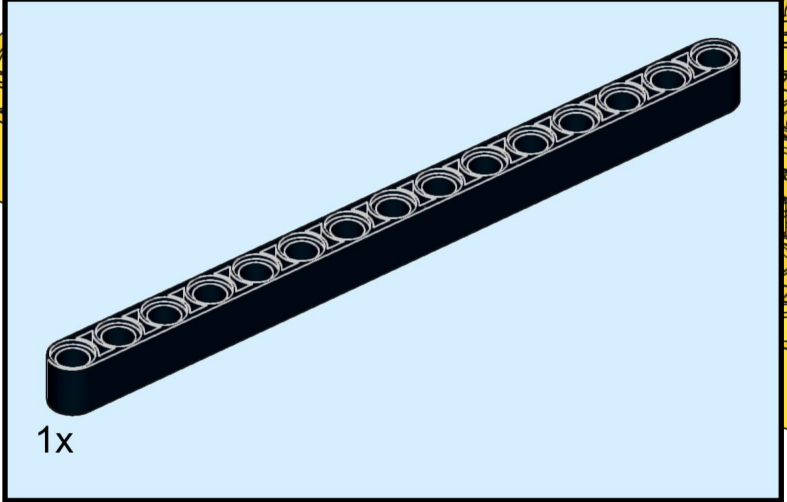
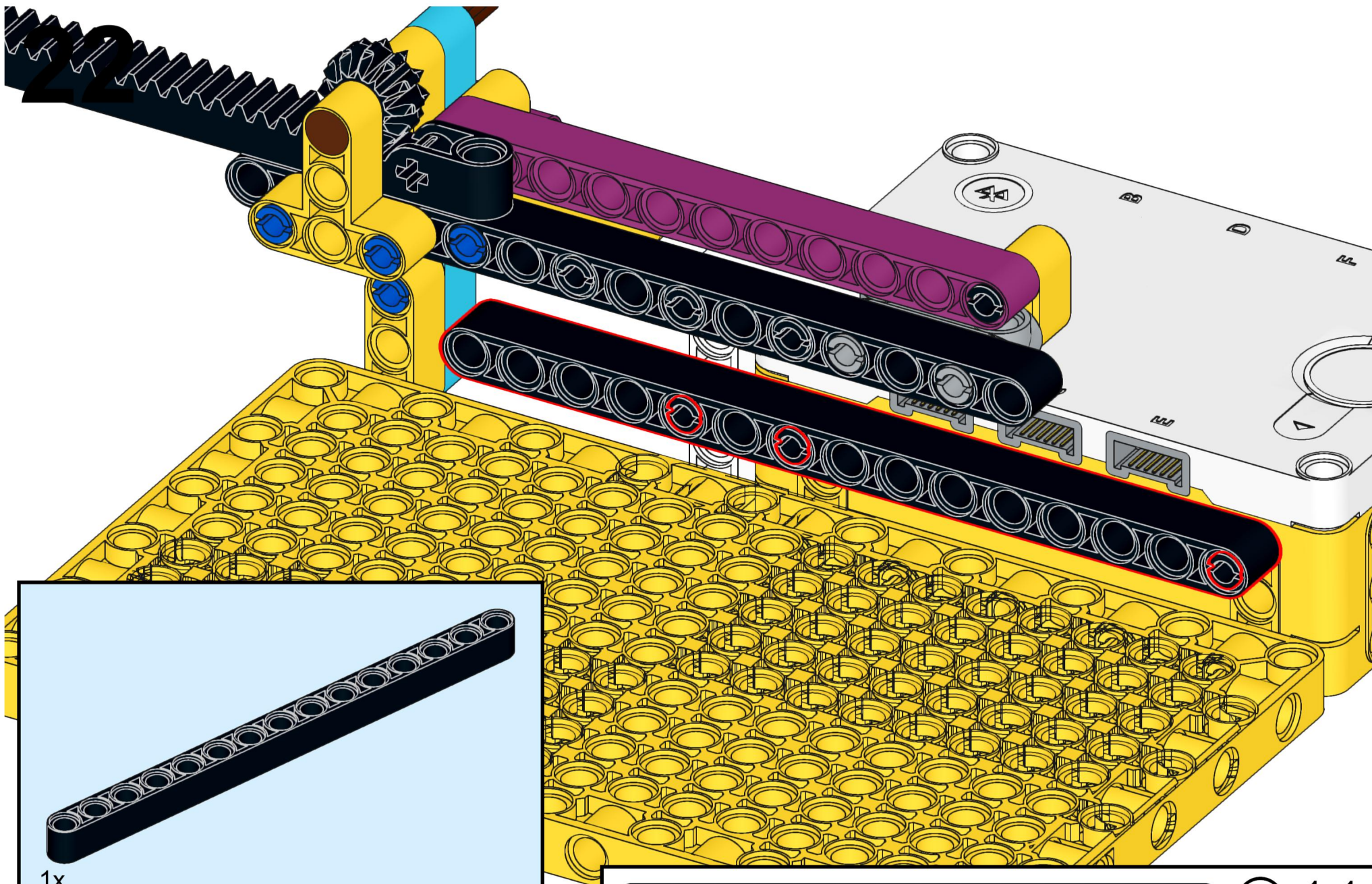




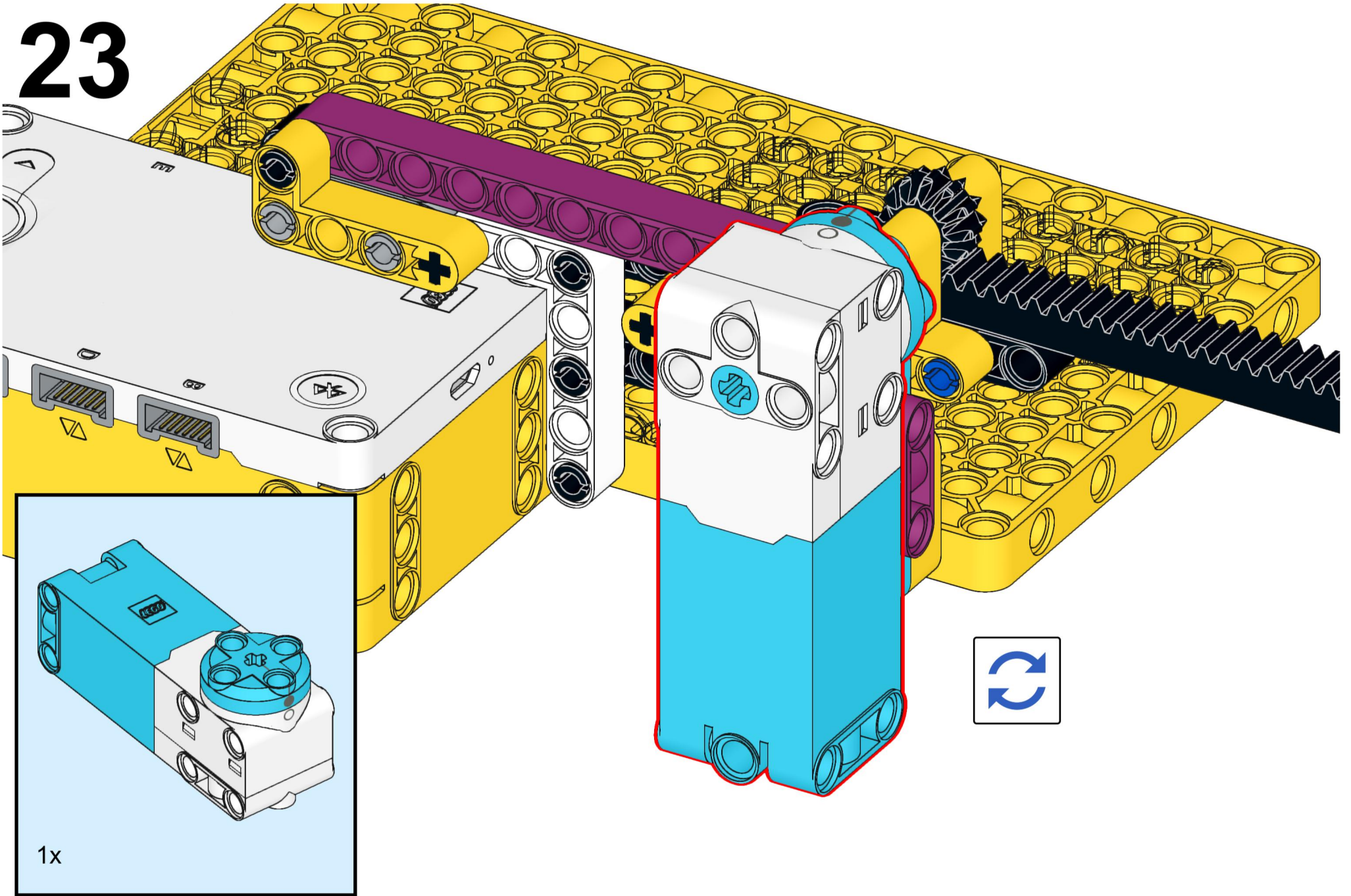
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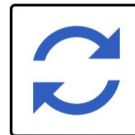




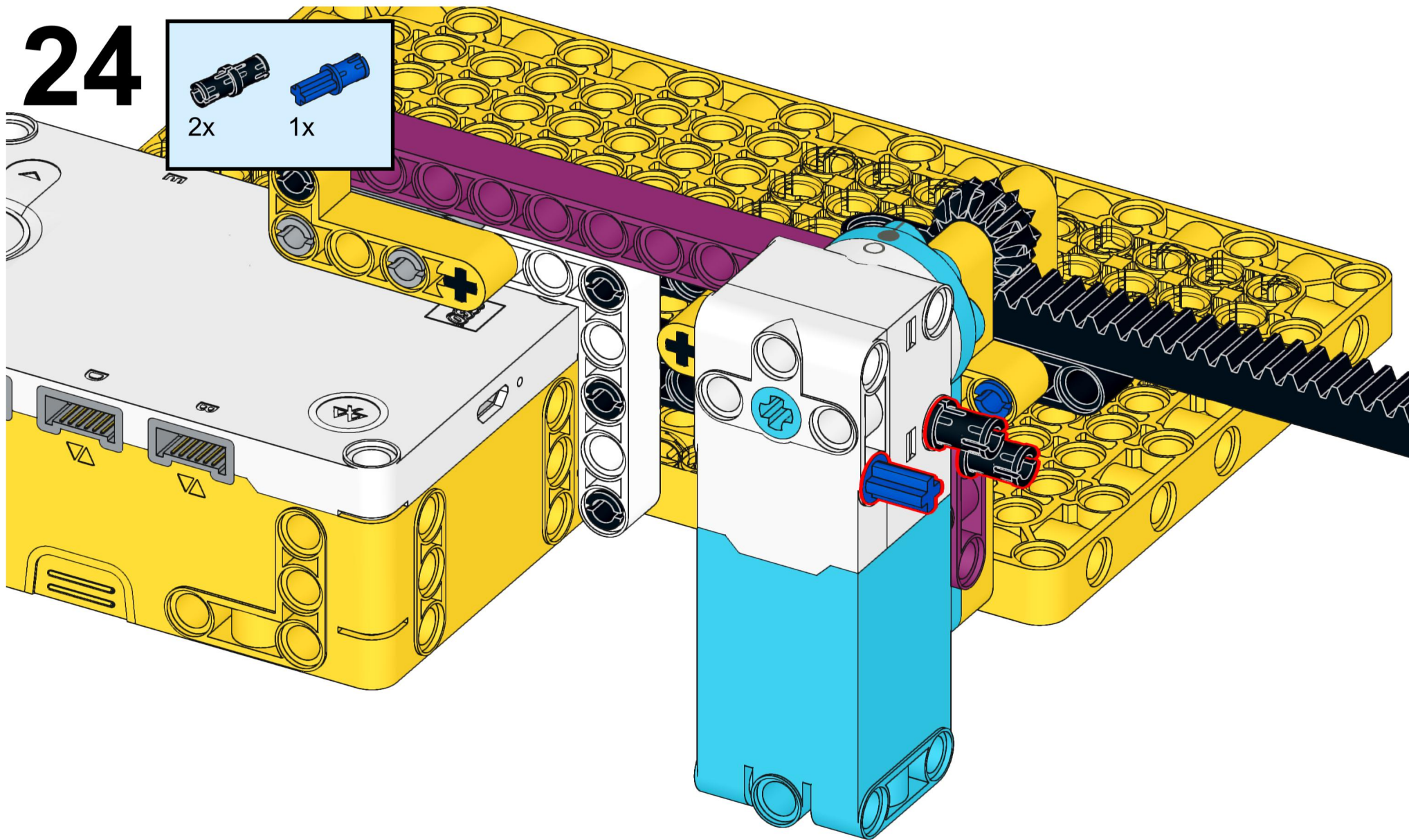
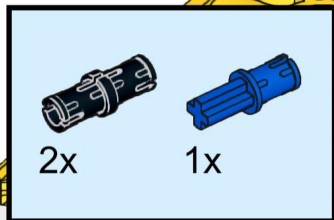
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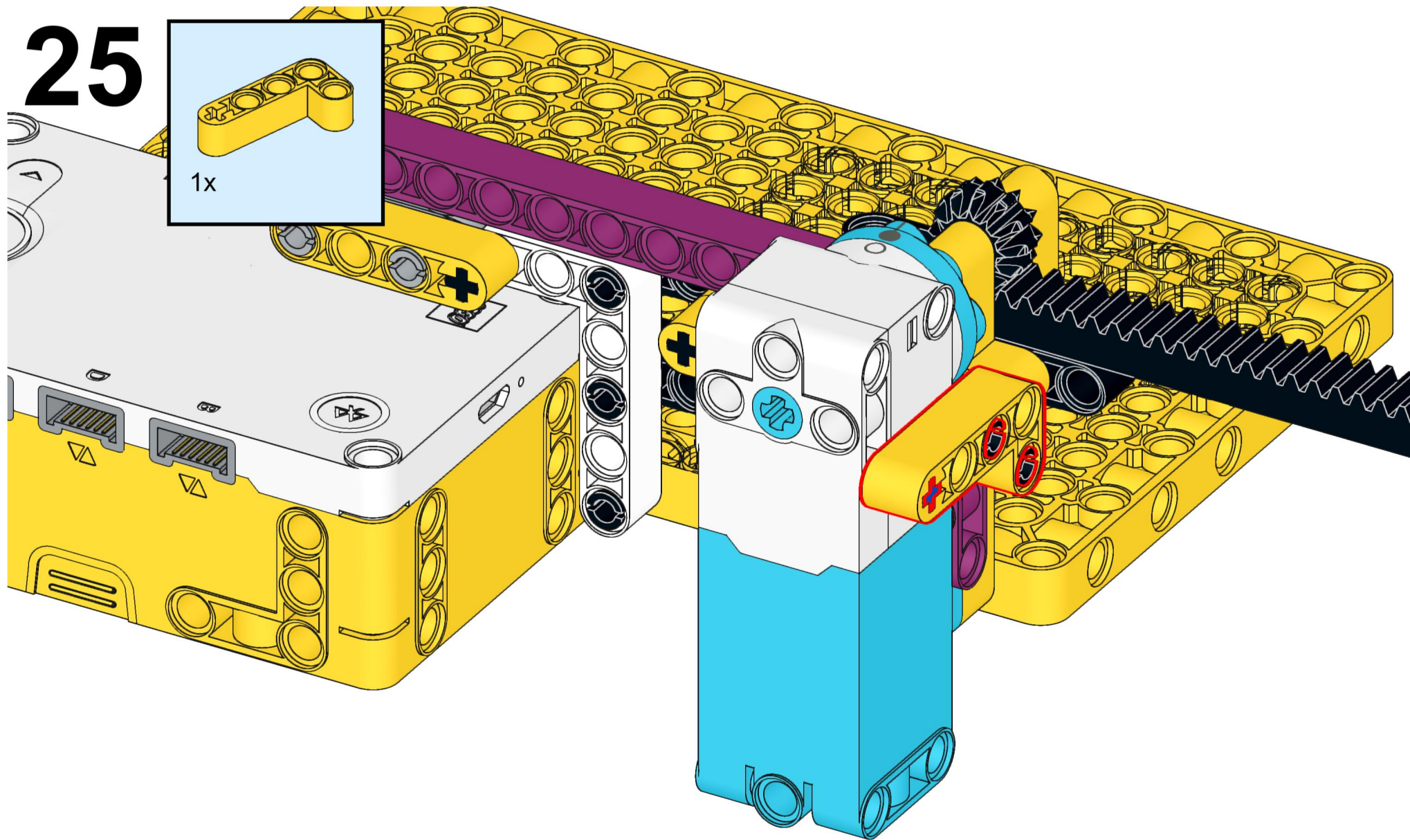
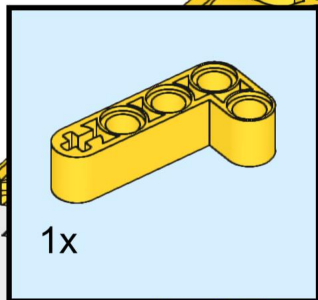
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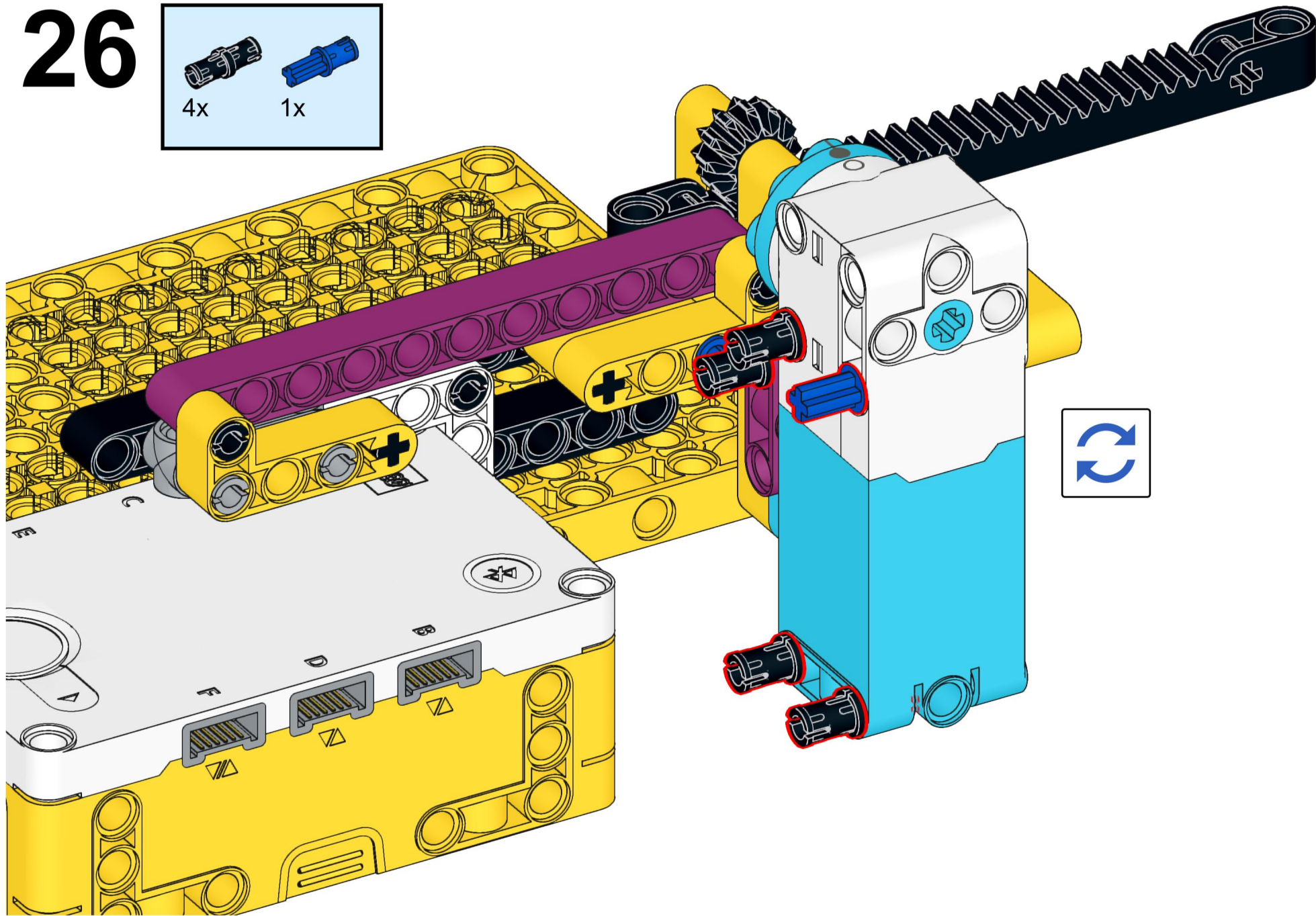
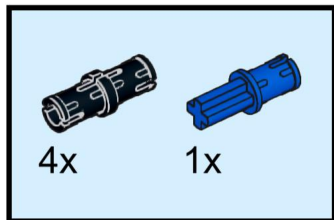
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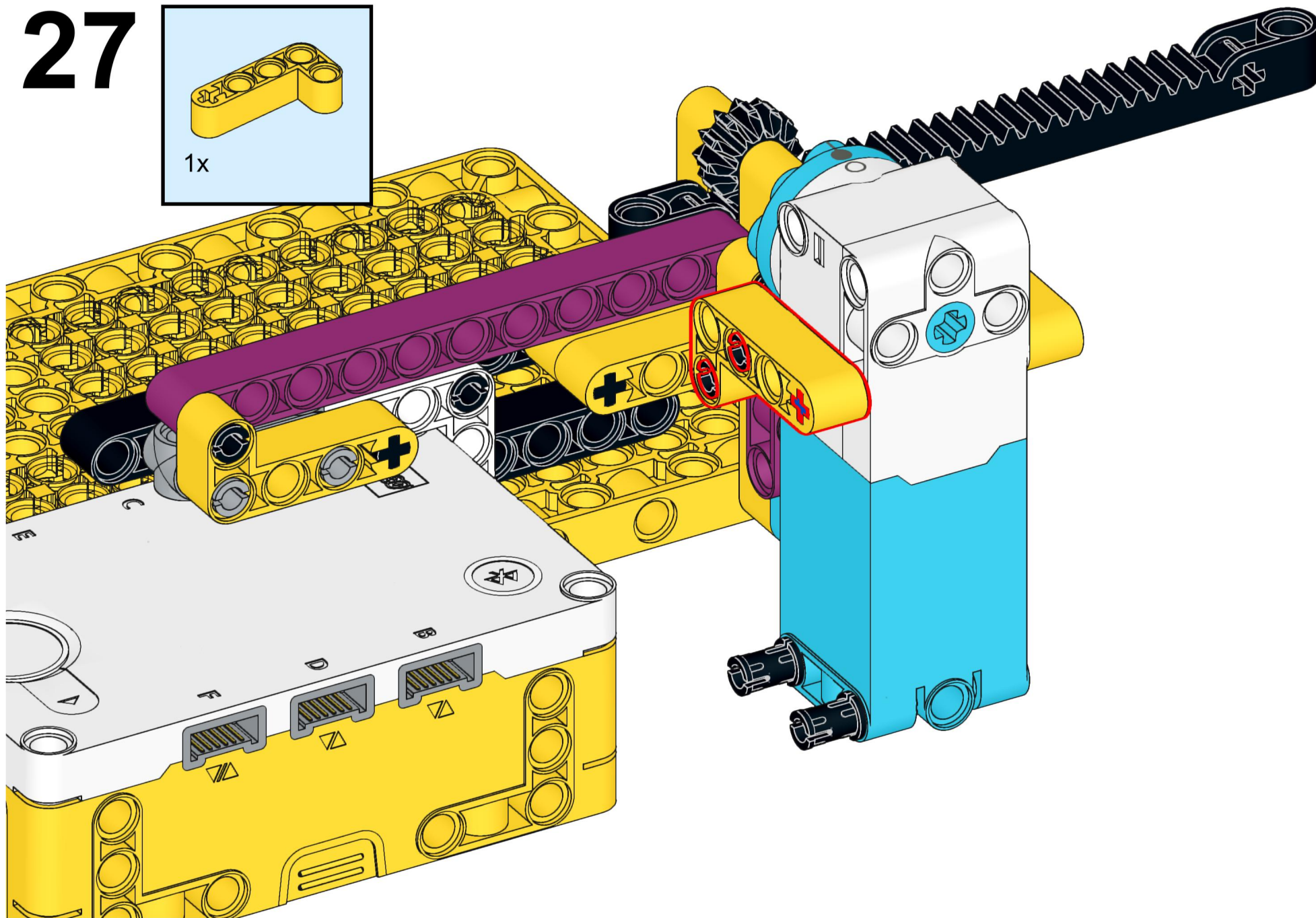
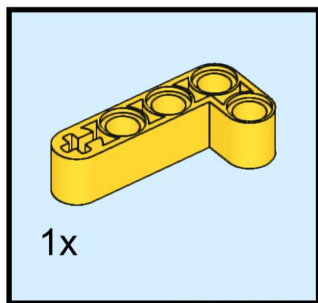
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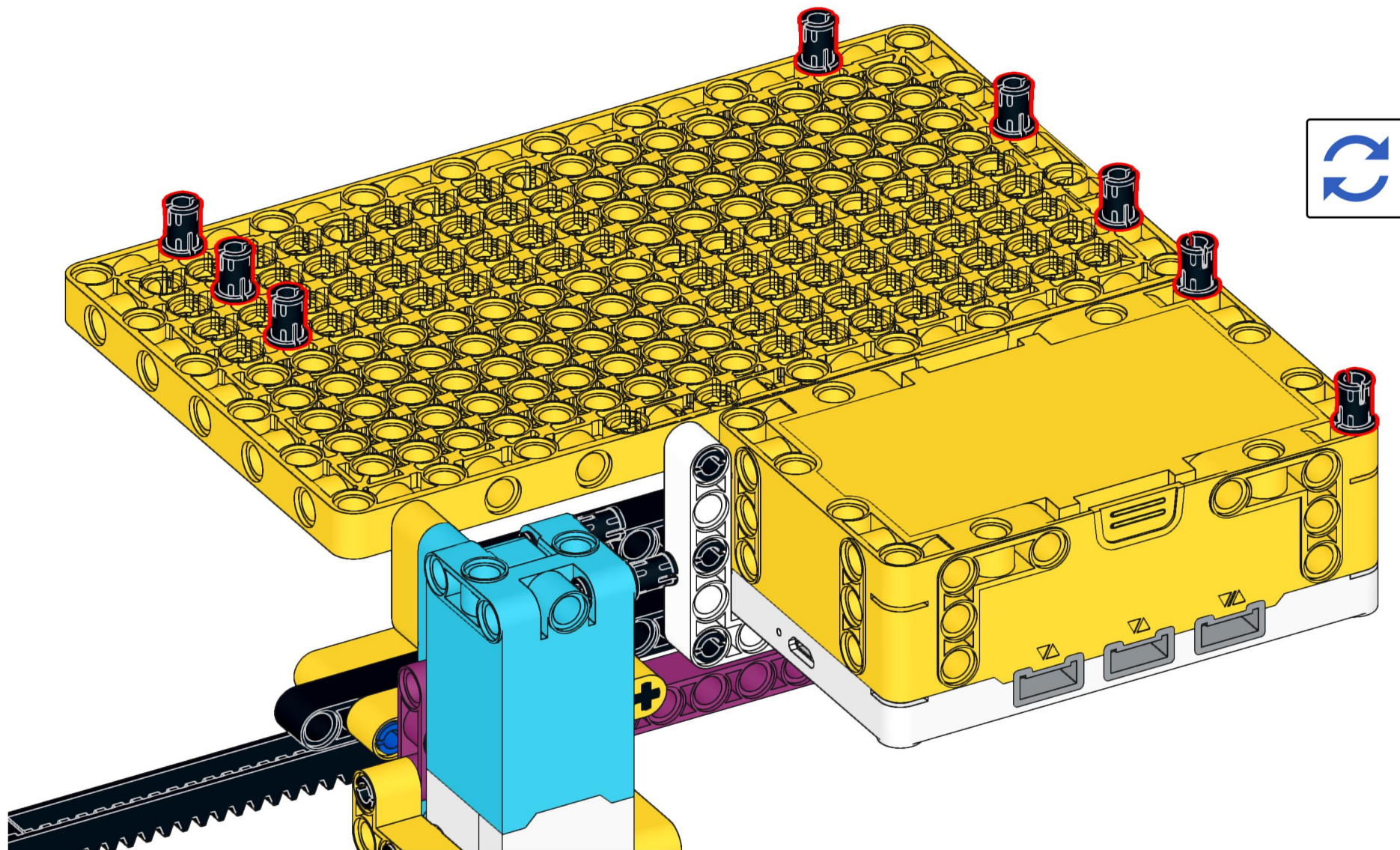
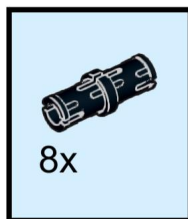
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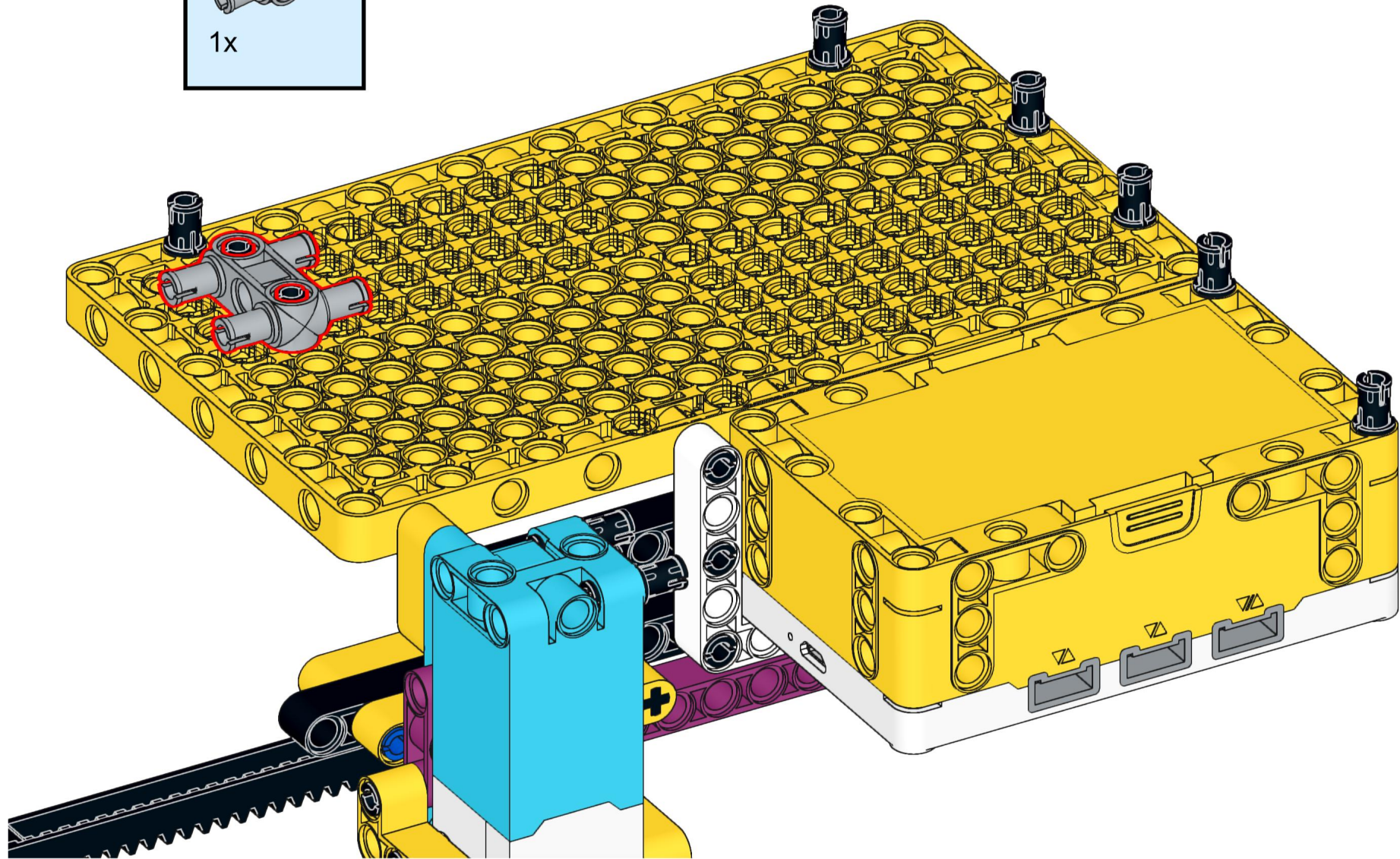
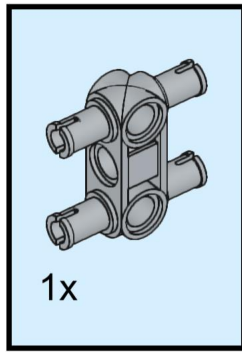
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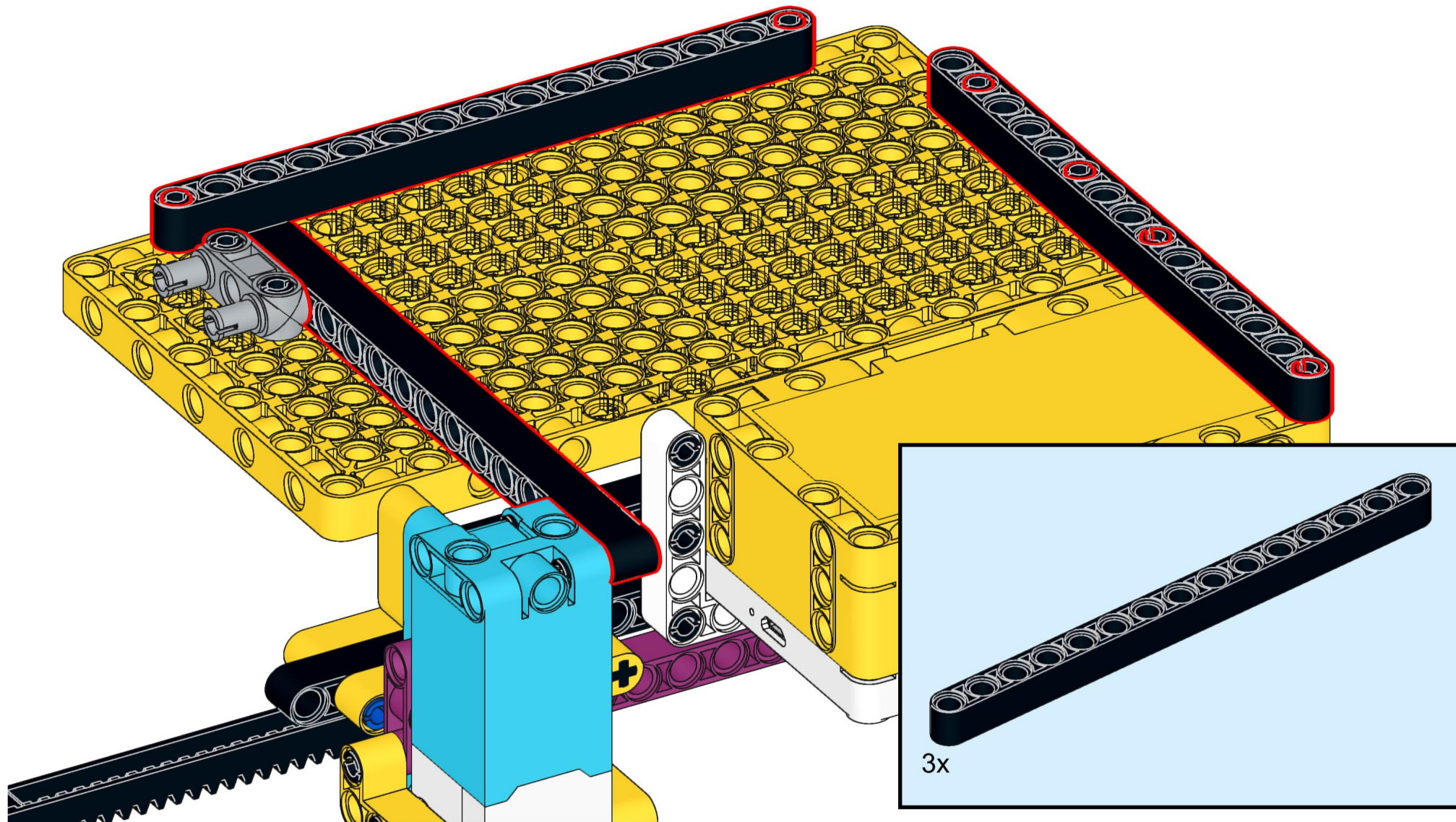
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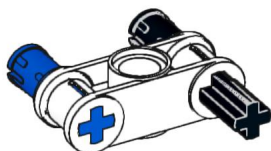
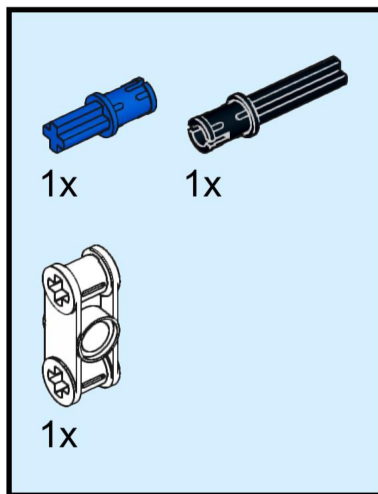
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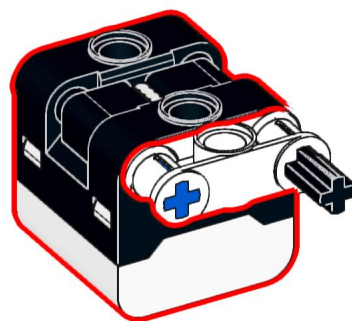
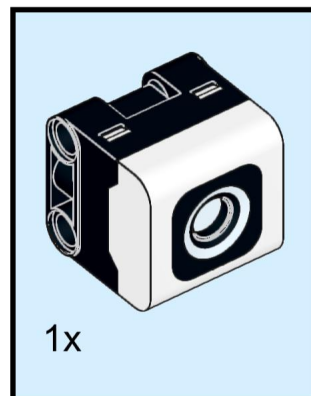
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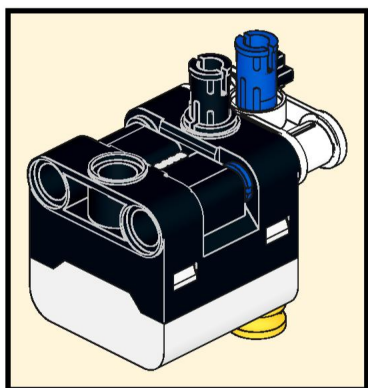
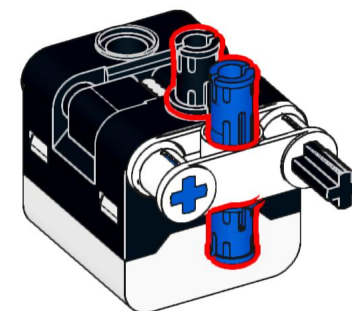
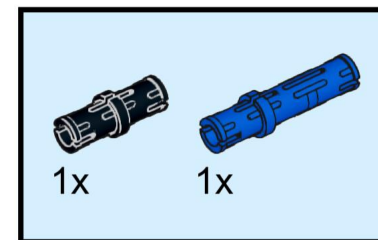
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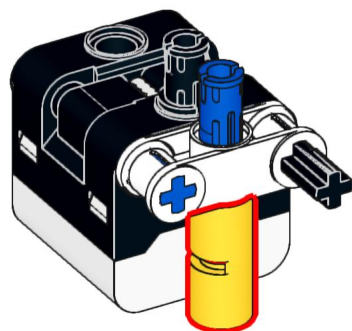
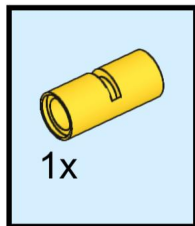
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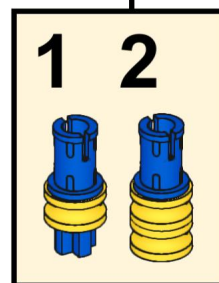
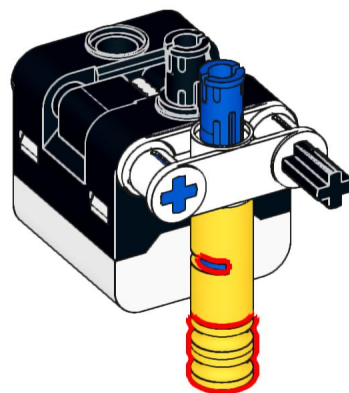
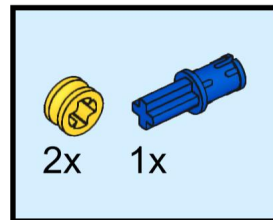
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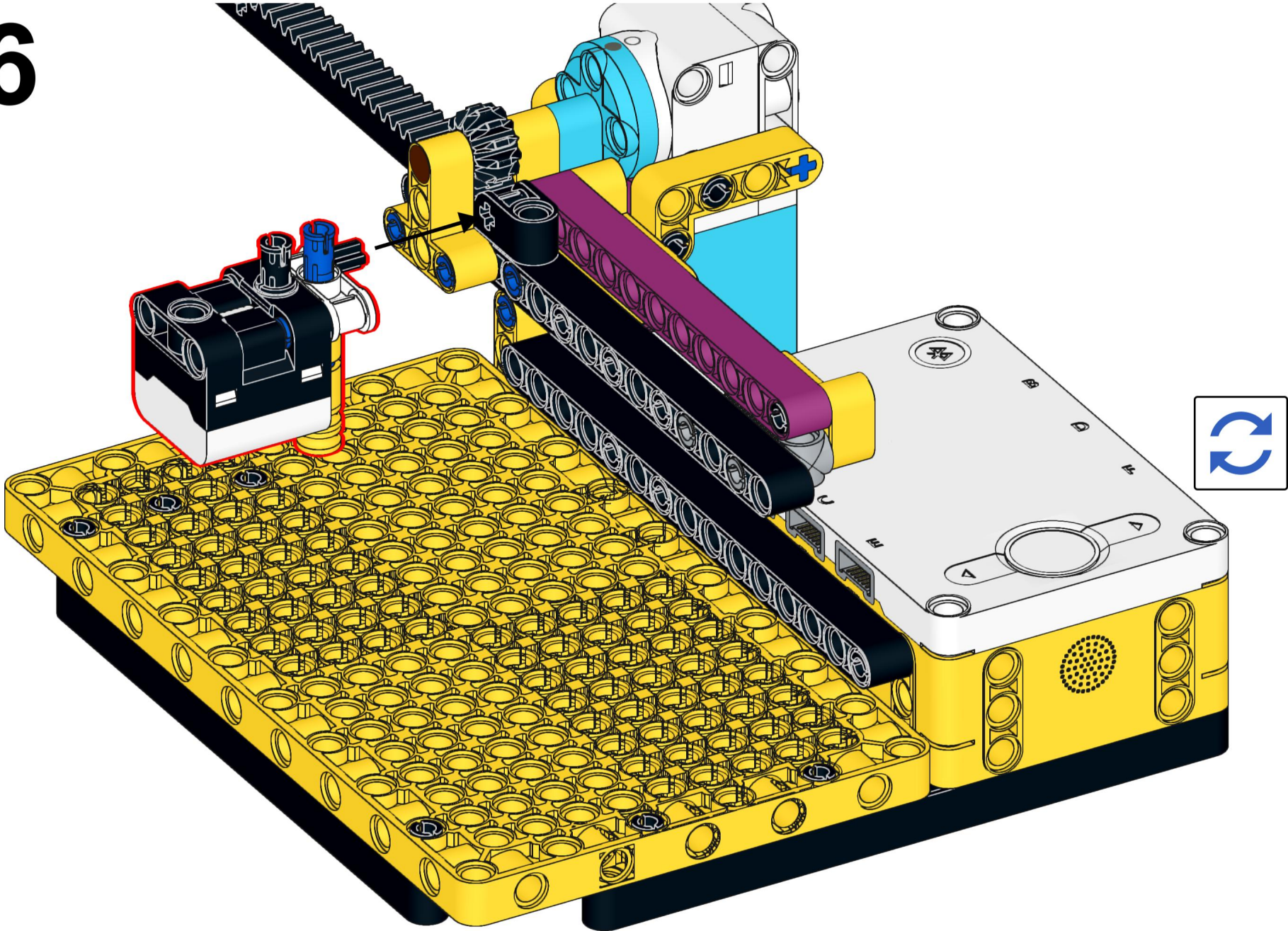
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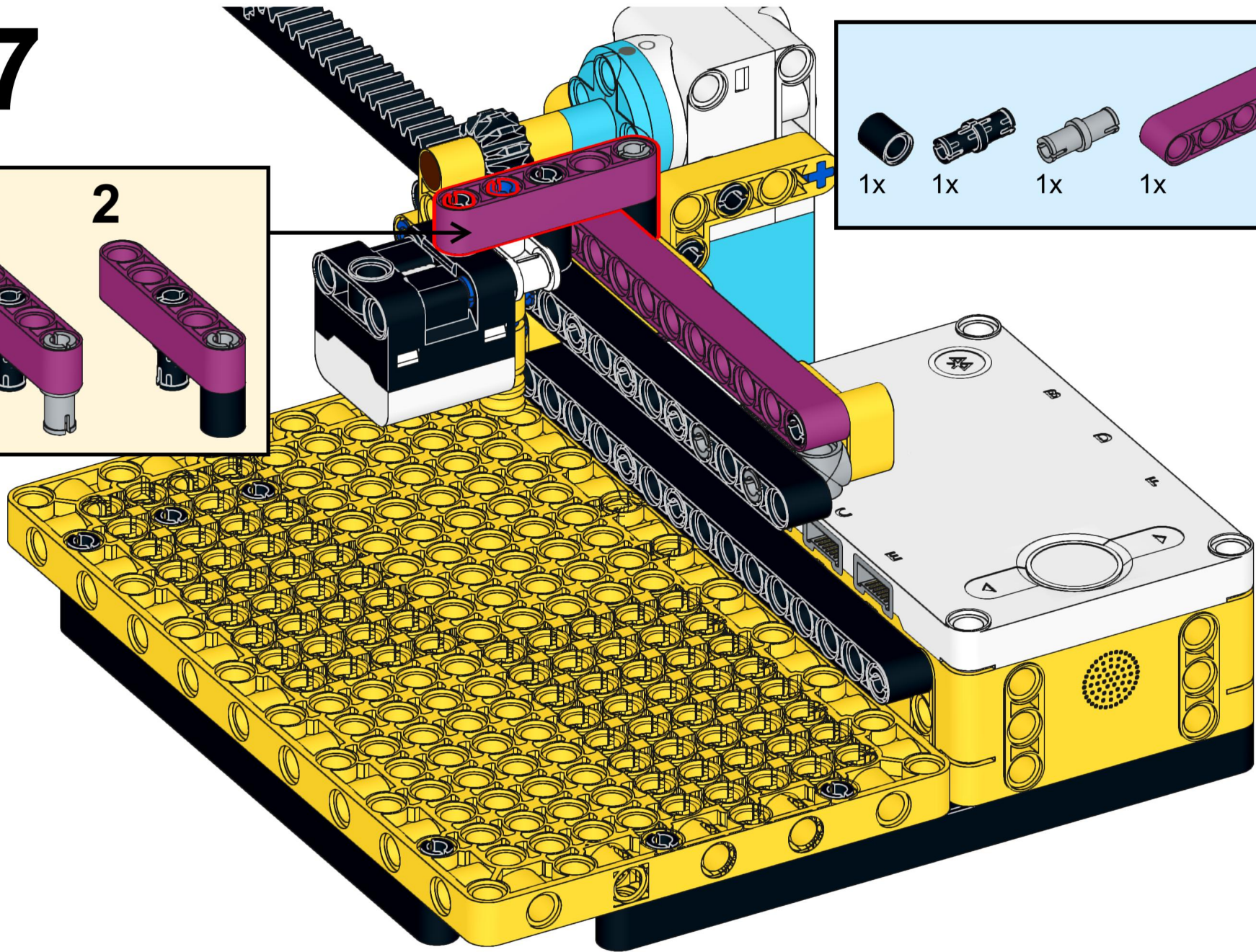
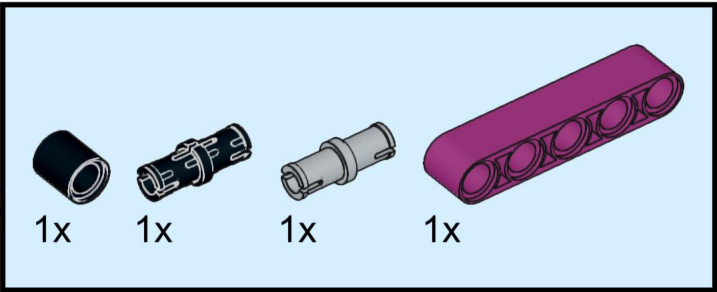
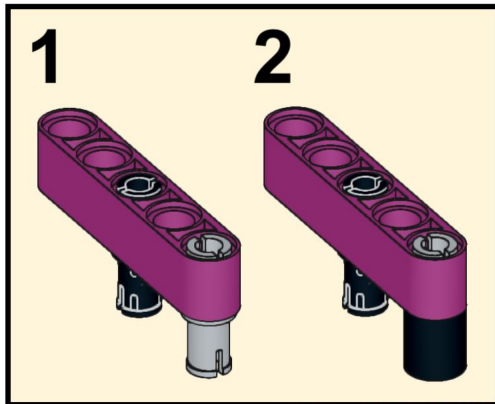
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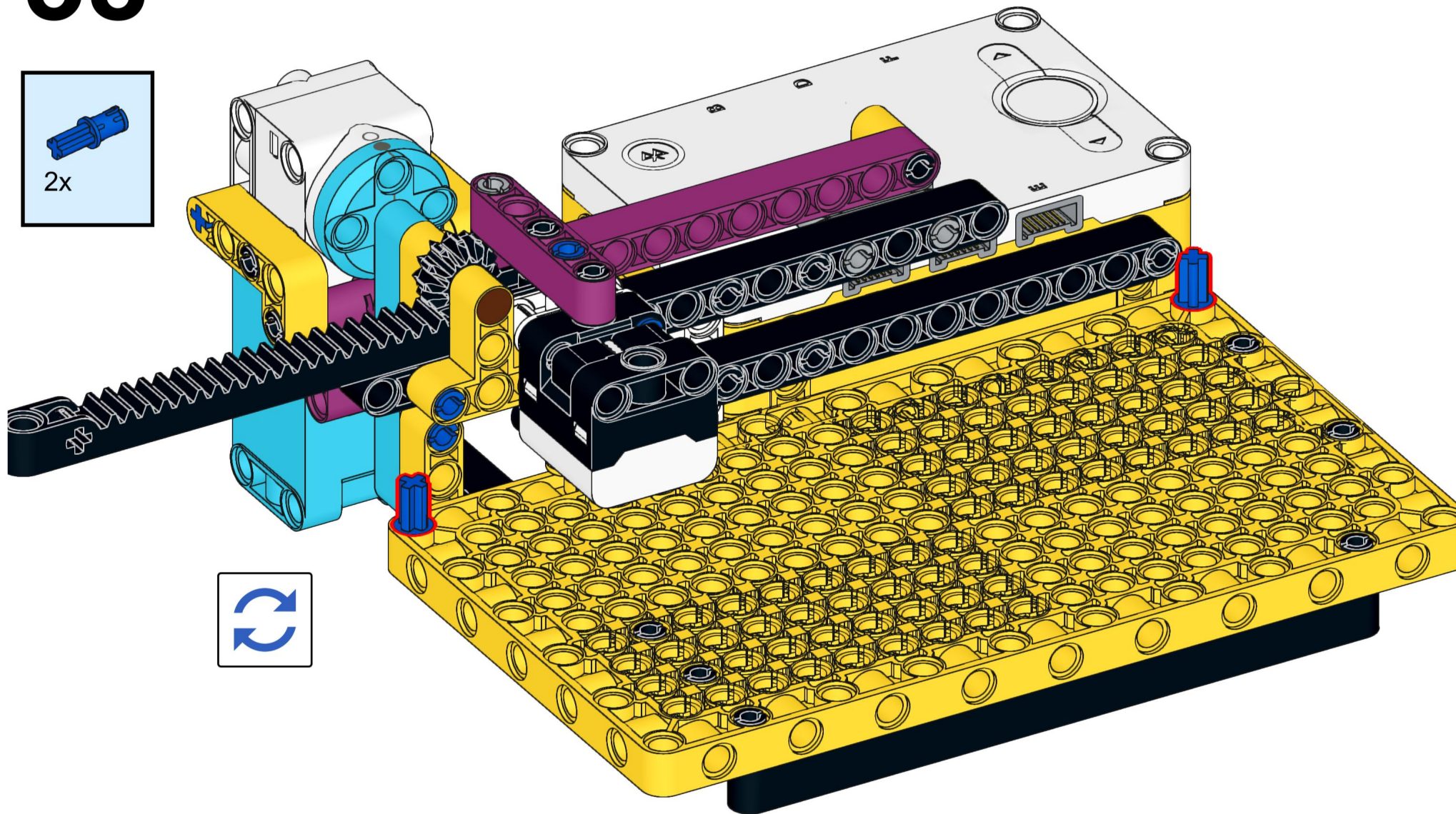
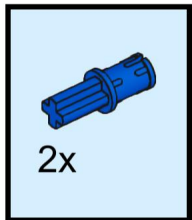
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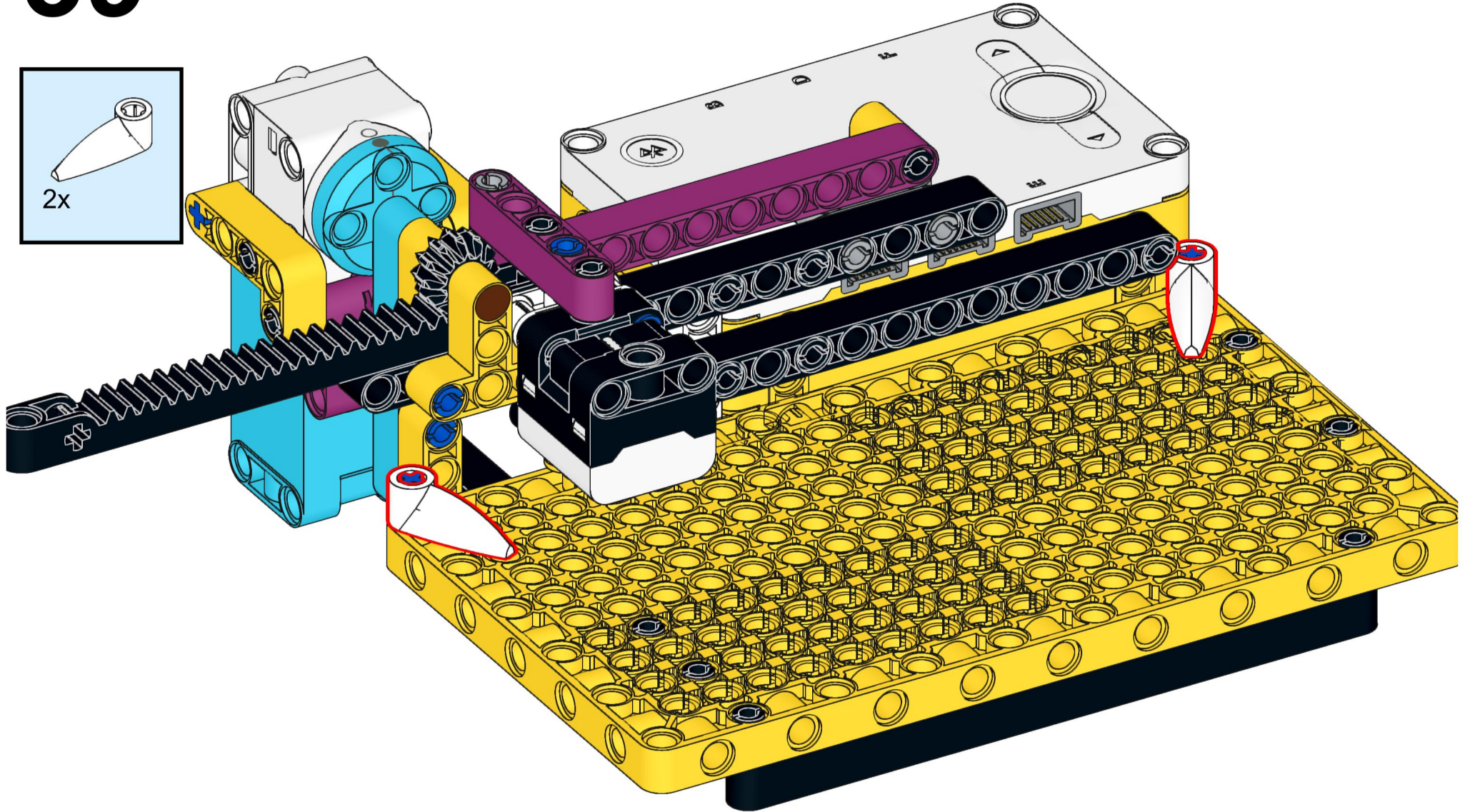
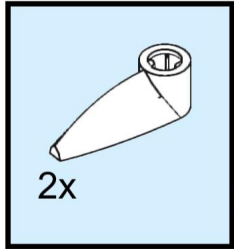
37



38



39



```
when program starts
  delete all of readouts
  clear line graph
  B set motors to brake at stop
  B start motor
  wait 0.4 seconds
  wait until 80 < abs of B power
  B stop motor
  B set relative position to 0
  B set motors to hold position at stop
  B go shortest path to position 0
  repeat 120
    B run for 5 degrees
    wait .25 seconds
    add F reflected light to readouts
    plot F reflected light to line
  B go to relative position 0 at 100 % speed
```

The image shows a sequence of block-based code for a program. It begins with a 'when program starts' block, followed by 'delete all of readouts' and 'clear line graph'. The motor is then set to 'brake at stop' and 'start motor'. A 'wait 0.4 seconds' block is followed by a 'wait until' loop that checks if the absolute value of the motor's power is greater than 80. Once this condition is met, the motor is stopped, its relative position is set to 0, and the motors are set to 'hold position at stop'. The motor then moves to the 'shortest path' to position 0. A 'repeat' loop runs 120 times, each iteration consisting of running the motor for 5 degrees, waiting for 0.25 seconds, adding the 'reflected light' sensor reading to the 'readouts', and plotting the 'reflected light' reading on a 'line'. Finally, the motor is moved to relative position 0 at 100% speed.