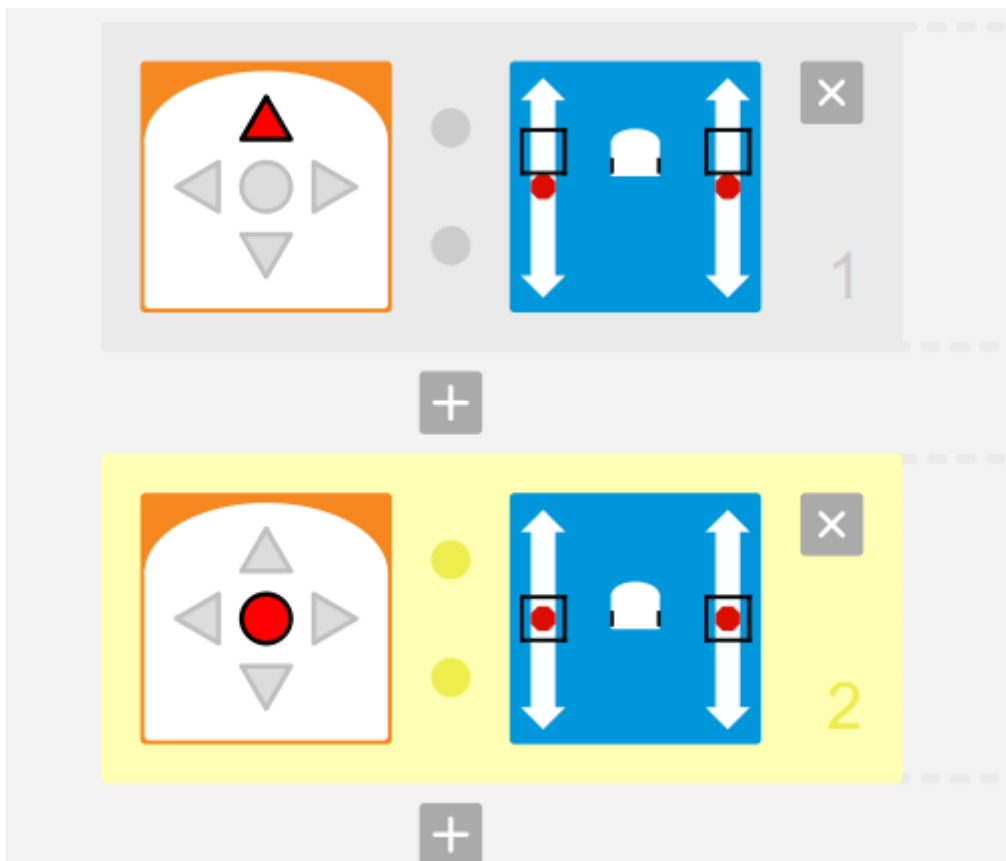


Mission 1 :

Flèche avant : Thymio avance.

Rond central : Thymio stop.



```
onevent buttons
when button.forward == 1 do
motor.left.target = 200
motor.right.target = 200
emit pair_run 0
end
when button.center == 1 do
motor.left.target = 0
motor.right.target = 0
emit pair_run 1
end
```

### Mission 2 :

Flèche avant : Thymio avance.

Rond central : Thymio stop.

Une surface noire : Thymio stop.

onevent buttons

when button.forward == 1 do

motor.left.target = 200

motor.right.target = 200

emit pair\_run 0

end

when button.center == 1 do

motor.left.target = 0

motor.right.target = 0

emit pair\_run 1

end

onevent prox

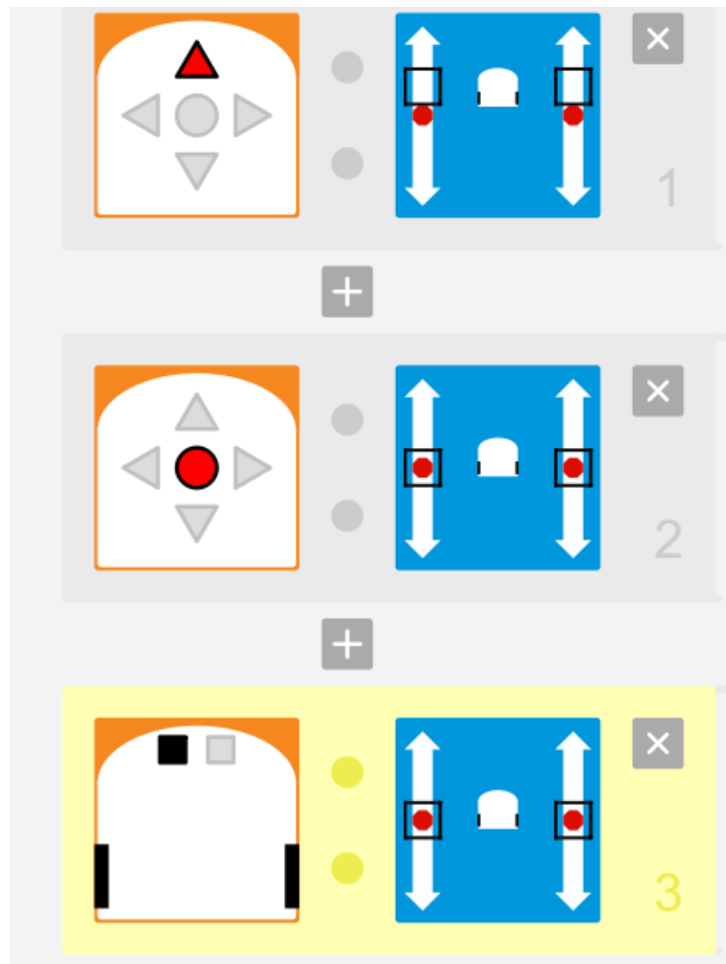
when prox.ground.delta[0] <= 400 do

motor.left.target = 0

motor.right.target = 0

emit pair\_run 2

end



### Mission 3 :

Flèche avant : Thymio avance.

Rond central : Thymio stop.

Une surface noire : Thymio Thymio recule.

onevent buttons

```
when button.forward == 1 do
```

```
  motor.left.target = 500
```

```
  motor.right.target = 500
```

```
  emit pair_run 0
```

```
end
```

```
when button.center == 1 do
```

```
  motor.left.target = 0
```

```
  motor.right.target = 0
```

```
  emit pair_run 1
```

```
end
```

onevent prox

```
when prox.ground.delta[0] <= 400
```

```
and prox.ground.delta[1] <= 400 do
```

```
  call leds.bottom.left(0,0,0)
```

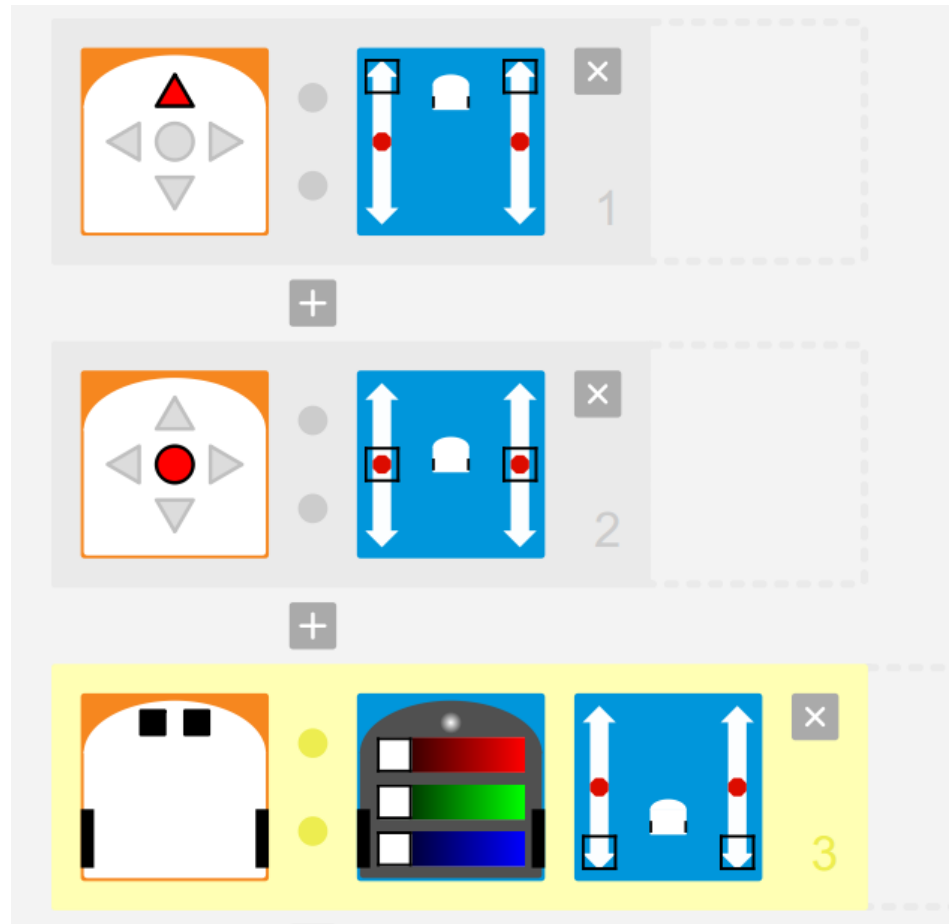
```
  call leds.bottom.right(0,0,0)
```

```
  motor.left.target = -500
```

```
  motor.right.target = -500
```

```
  emit pair_run 2
```

```
end
```



#### Mission 4 :

Flèche avant : Thymio avance.

Rond central : Thymio stop.

Une surface noire : Thymio recule.

Détection d'un obstacle derrière : Thymio stop.

onevent buttons

```
when button.forward == 1 do
```

```
  motor.left.target = 200
```

```
  motor.right.target = 200
```

```
  emit pair_run 0
```

```
end
```

```
when button.center == 1 do
```

```
  motor.left.target = 0
```

```
  motor.right.target = 0
```

```
  emit pair_run 1
```

```
end
```

onevent prox

```
when prox.ground.delta[0] <= 400 and
```

```
prox.ground.delta[1] <= 400 do
```

```
  motor.left.target = -200
```

```
  motor.right.target = -200
```

```
  emit pair_run 2
```

```
end
```

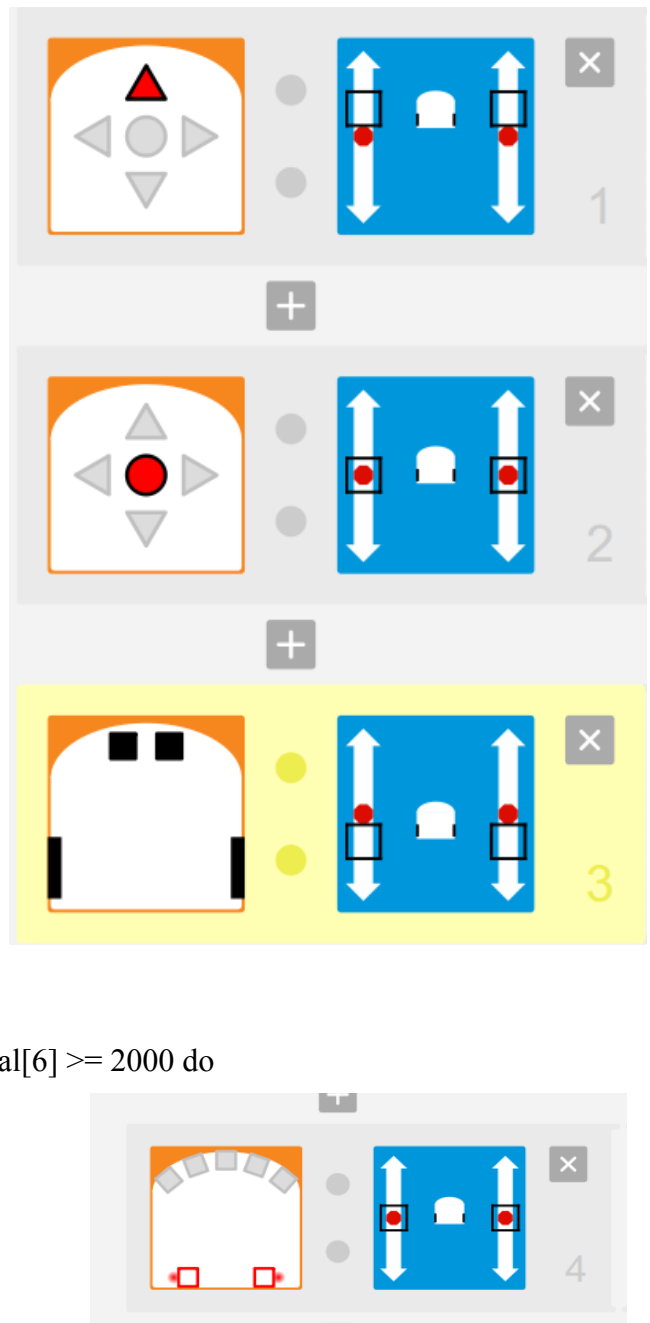
```
when prox.horizontal[5] >= 2000 and prox.horizontal[6] >= 2000 do
```

```
  motor.left.target = 0
```

```
  motor.right.target = 0
```

```
  emit pair_run 3
```

```
end
```



### Mission 5 :

Flèche avant : Thymio avance et est vert.

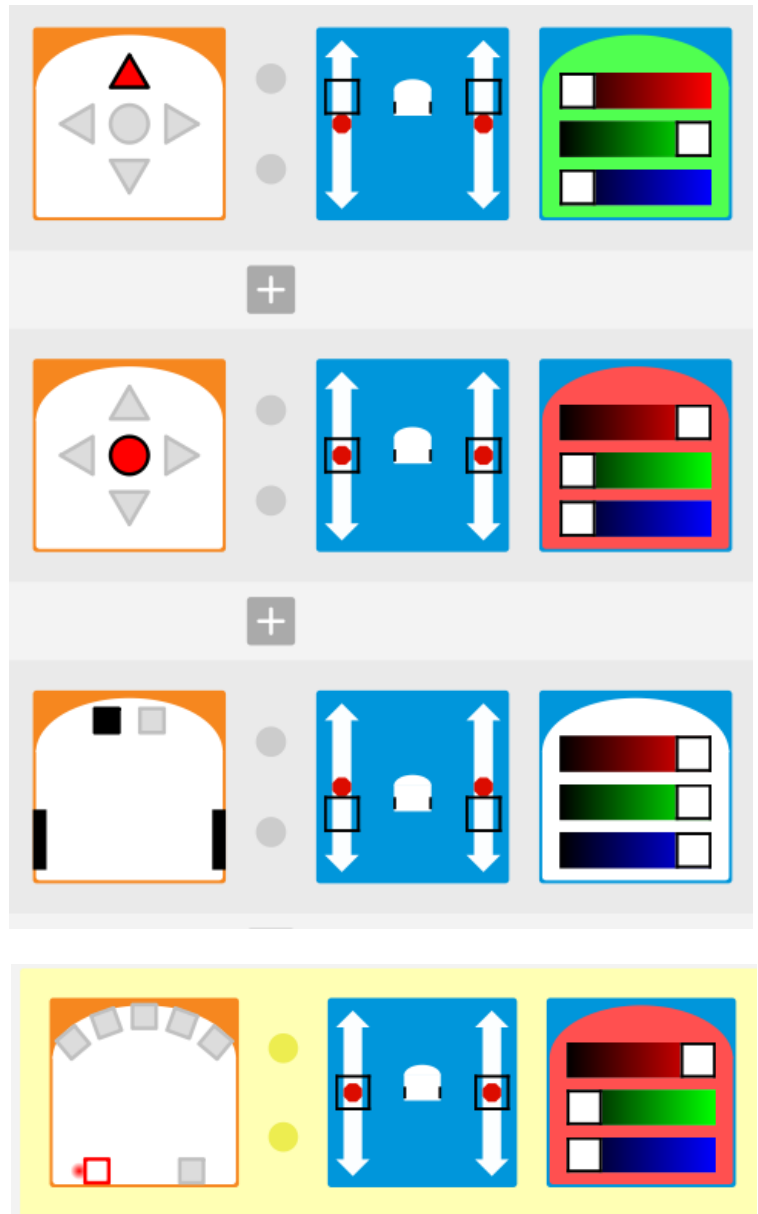
Rond central : Thymio stop et est rouge.

Une surface noire : Thymio recule et est blanc.

Détection d'un obstacle derrière : Thymio stop et est rouge.

```
onevent buttons
when button.forward == 1 do
motor.left.target = 200
motor.right.target = 200
call leds.top(0,32,0)
emit pair_run 0
end
when button.center == 1 do
motor.left.target = 0
motor.right.target = 0
call leds.top(32,0,0)
emit pair_run 1
end
```

```
onevent prox
when prox.ground.delta[0] <= 400 do
motor.left.target = -200
motor.right.target = -200
call leds.top(32,32,32)
emit pair_run 2
end
when prox.horizontal[5] >= 2000 do
motor.left.target = 0
motor.right.target = 0
call leds.top(32,0,0)
emit pair_run 3
end
```



Mission 6 :

Thymio suit la limite entre du blanc et du noir.

```
onevent prox
when prox.ground.delta[1] <= 400 do
motor.left.target = 200
motor.right.target = 0
emit pair_run 0
end
when prox.ground.delta[0] >= 450 do
motor.left.target = 0
motor.right.target = 200
emit pair_run 1
end
when prox.ground.delta[0] <= 400 and
prox.ground.delta[1] >= 450 do
motor.left.target = 150
motor.right.target = 150
emit pair_run 2
end
```

```
onevent buttons
when button.center == 1 do
motor.left.target = 0
motor.right.target = 0
emit pair_run 3
end
```

