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**Arduino Roboter «vereinfachte Version für die Primarschule»**

* Füge diesen XML-Code in den grafischen online Editor ein: [mach.pglu.ch](https://mach.pglu.ch/)
* Anleitung: [PGLU.CH > ANLEITUNG > EDITOR > PROGRAMME IMPORTIEREN](https://pglu.ch/anleitung-app/#import)
* Zum Kopieren: 3-fach-Klick in den Code

<xml xmlns="https://developers.google.com/blockly/xml"><variables><variable id="lO0ZYE\*d3-TBXT4=/F%w">LED</variable><variable id="0z{{\*X:B1%h{p$#~9jog">Intervall in ms</variable><variable id="?~`j6li~gz]E9ASa.KQP">Anzahl</variable><variable id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</variable><variable id="\*:3e.esi^B`J%$5)X12H">Zeit in ms</variable><variable id="LxkGe)=JaZ:.FWq%8/{%">Start-Tempo</variable><variable id="QmpV861a}-ED`kw\_!OUj">End-Tempo</variable><variable id="5MT4jvb3P0}5#GS.D,87">Korrektur M1</variable><variable id="|~,OsB~H~X)([2gt$CLf">Distanz in cm</variable><variable id="HJYdxPCN]:ZCMUgos.h8">Korrektur M2</variable><variable id="Gt#^=(OVC9s1jWO6hUFu">Zeitstempel</variable><variable id=".gklvtf4@5gvI|=mU7D/">Verstrichene Zeit</variable></variables><block type="basic\_comment" id="cKJe5~`~{^$2AiMA6kLi" x="329" y="-762"><field name="COMMENT">ARDUINO ROBOTER - VEREINFACHTE PROGRAMMIERUNG FÜR DIE PRIMARSCHULE</field></block><block type="basic\_comment" id="`5efDATZ#^7.R5JYY4%P" x="-1167" y="-631"><field name="COMMENT">\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*Setze diese Blöcke in den Hauptloop ein! \*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*Kopiere sie mit long-touch, ctrl-c oder Rechtsklick\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*</field></block><block type="basic\_comment" id="VqL}4}2k,Ds[ivNf7qzU" x="328" y="-701"><field name="COMMENT">Setze die Blöcke auf der linken Seite in den Hauptloop ein&amp;#10;\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*&amp;#10;Das Tempo kann zwischen -100% und 100% liegen&amp;#10;&amp;#10;S1+M1 sind in Fahrtrichtung links&amp;#10;S2+M2 sind in Fahrtrichtung rechts</field></block><block type="basic\_comment" id="B`v=%nZQTs9uqKC\_`/e=" x="-1168" y="-589"><field name="COMMENT">Einfache Logik mit Tastsensor</field></block><block type="basic\_comment" id="Fr+\_sYSFi!S}Zzwzl!cU" x="-558" y="-591"><field name="COMMENT">Einfacher Fahrbefehl ohne zeitliche Begrenzung</field></block><block type="logic\_if" id="fS!izV9^cvT:M?yjRz0," x="-1126" y="-534"><mutation xmlns="http://www.w3.org/1999/xhtml" else="1"></mutation><value name="IF0"><block type="sensor\_test\_state" id="TS!4=S?)la5cQ-^G^tH0"><field name="MODE">STANDARD</field><value name="SENSOR"><block type="sensor\_pin" id="5REmP!Kp4h]j.cPr]$~k"><field name="SENSOR">SENSOR2</field></block></value><value name="STATE"><block type="basic\_digital\_state" id="U@/ti%BCp[evF|wvYL,)"><field name="STATE">LOW</field></block></value></block></value></block><block type="procedures\_callnoreturn" id="a@i+Fy#h71~G^\_1\*h\_f2" x="-516" y="-538"><mutation name="fahre immer gerade, bis ein anderer Fahrbefehl kommt"><arg name="Tempo in %"></arg></mutation><value name="ARG0"><block type="math\_number" id="BIx$lH:XFzl3D-9))sdN"><field name="NUM">100</field></block></value></block><block type="basic\_main\_loop" id="G\*CnBl/}.#[Uu3$r65YB" deletable="false" x="327" y="-536"><value name="BLINK"><block type="basic\_blinkcode" id="dNza0.A\_^`:Gp@0E\_6sk"><field name="SHORT">1</field><field name="LONG">1</field></block></value></block><block type="basic\_comment" id="wNq~M0$?YKLQa#!l0{\*1" x="-553" y="-464"><field name="COMMENT">Einfache Fahrbefehle mit zeitlicher Begrenzung</field></block><block type="logic\_if" id="2.L}).|(Xl6P2^YG{WCn" x="-1123" y="-388"><mutation xmlns="http://www.w3.org/1999/xhtml" else="1"></mutation><value name="IF0"><block type="sensor\_test\_state" id="i8.G{kmK)4IbIU8nsvGi"><field name="MODE">STANDARD</field><value name="SENSOR"><block type="sensor\_pin" id="ggQwb,]FtzFlrSIF7mVo"><field name="SENSOR">SENSOR1</field></block></value><value name="STATE"><block type="basic\_digital\_state" id="NalWBdX{s![vB#1`3iQZ"><field name="STATE">LOW</field></block></value></block></value></block><block type="procedures\_callnoreturn" id="[TP2I(#RMWXrM@/:J.j@" x="-514" y="-415"><mutation name="drehe rechts"><arg name="Zeit in ms"></arg><arg name="Tempo in %"></arg></mutation><value name="ARG0"><block type="math\_number" id="nzkzz5Rn;6pcaF,#^ErQ"><field name="NUM">500</field></block></value><value name="ARG1"><block type="math\_number" id="5:brD?jZ3[-m:;zY-{kc"><field name="NUM">100</field></block></value></block><block type="procedures\_callnoreturn" id="$`347Mu.zr?u6er\*B.J=" x="-512" y="-341"><mutation name="drehe links"><arg name="Zeit in ms"></arg><arg name="Tempo in %"></arg></mutation><value name="ARG0"><block type="math\_number" id="agn||YCF+(c,}`)g}\_32"><field name="NUM">500</field></block></value><value name="ARG1"><block type="math\_number" id="7vk+H8b.5JynBsa7/eiH"><field name="NUM">100</field></block></value></block><block type="basic\_comment" id="#X\_Z#.vzvfwRBM~8Z:7b" x="-1164" y="-177"><field name="COMMENT">Erweiterte Logik mit Ultraschallsensor</field></block><block type="basic\_comment" id="i/j1AzAmu8fd+4gdu/Lv" x="-544" y="-187"><field name="COMMENT">Erweiterte Fahrbefehle mit zeitlicher Begrenzung</field></block><block type="logic\_if" id="bkrsaCVWd}-g)nz]%hj6" x="-1117" y="-124"><mutation xmlns="http://www.w3.org/1999/xhtml" else="1"></mutation><value name="IF0"><block type="logic\_compare" id="OS:#.-/ZFWnsJ6EBYX9F"><field name="OP">LT</field><value name="A"><block type="procedures\_callreturn" id="fFVUZ3cT7TMOL)0:O|YY"><mutation name="Gemessene Distanz in cm mit Ultraschallsensor an S3"></mutation></block></value><value name="B"><block type="math\_number" id="#?lwsS2O.ZEvZTr7Sl|o"><field name="NUM">15</field></block></value></block></value></block><block type="procedures\_callnoreturn" id="Zn/FvMYk\*7jx-!px[2zv" x="-505" y="-136"><mutation name="fahre gerade"><arg name="Zeit in ms"></arg><arg name="Tempo in %"></arg></mutation><value name="ARG0"><block type="math\_number" id="fOUgB91o^b\*x|W8w[xw1"><field name="NUM">1000</field></block></value><value name="ARG1"><block type="math\_number" id="D7,~^b,6G@#(b|\_6H{Mt"><field name="NUM">100</field></block></value></block><block type="procedures\_callnoreturn" id="cwSHM=}?FF#Qrtf{-f+g" x="-504" y="-57"><mutation name="beschleunige gerade"><arg name="Start-Tempo"></arg><arg name="End-Tempo"></arg><arg name="Zeit in ms"></arg></mutation><value name="ARG0"><block type="math\_number" id="?`+,n4.IVFCU[a0TegLc"><field name="NUM">0</field></block></value><value name="ARG1"><block type="math\_number" id="!IwDVS~))1):!/RZRNl)"><field name="NUM">100</field></block></value><value name="ARG2"><block type="math\_number" id="sZEb#Uz=1ybP3u}(NOaU"><field name="NUM">1000</field></block></value></block><block type="procedures\_callnoreturn" id="LKPNUtr%-DAtt`wNPQHC" x="-504" y="14"><mutation name="stoppe"><arg name="Zeit in ms"></arg></mutation><value name="ARG0"><block type="math\_number" id="aZe(riw:;\_fF\_!;@%6\_y"><field name="NUM">1000</field></block></value></block><block type="basic\_comment" id="Z.T%z)$q/PQeHgiys?X/" x="-1157" y="80"><field name="COMMENT">Dein Roboter fährt nicht schön geradeaus, weil ein Motor langsamer läuft?&amp;#10;\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*&amp;#10;Korrigiere die Motoren hier durch Verlangsamen eines Rades!&amp;#10;Reduziere dazu den Korrekturfaktor z.B. auf 0.95, um ein bestimmtes Rad zu verlangsamen&amp;#10;&amp;#10;M1 &lt; links rechts &gt; M2</field></block><block type="basic\_comment" id="YySlQc%T.yHW}Nu1m4w\*" x="-535" y="93"><field name="COMMENT">Erweiterte Fahrbefehle mit Ereignis-Begrenzung</field></block><block type="procedures\_callnoreturn" id="+5RvIzSL[k|Qym%Ib32D" x="-504" y="159"><mutation name="stoppe bis Sensor 1 oder 2 berührt werden"></mutation></block><block type="expert\_setup" id="n`^X=a^-s/deQxv!gyOB" x="-1125" y="224"><statement name="CODE"><block type="variables\_set" id="ogoAs~nAQ@y./\_;{#\*L`"><field name="VAR" id="5MT4jvb3P0}5#GS.D,87">Korrektur M1</field><value name="VALUE"><block type="math\_number" id="Wu3sirdS,Cy+Hx]eyb\_}"><field name="NUM">1</field></block></value><next><block type="variables\_set" id="$}2$uF4PGhI~$^d,HXmq"><field name="VAR" id="HJYdxPCN]:ZCMUgos.h8">Korrektur M2</field><value name="VALUE"><block type="math\_number" id="Dd7O+]Cw\_+DO-K$Xp;W0"><field name="NUM">1</field></block></value></block></next></block></statement></block><block type="basic\_comment" id="PU:f#eczq,Yeju4vc`E{" x="-531" y="228"><field name="COMMENT">Aktionen mit LED-Licht</field></block><block type="procedures\_callnoreturn" id="00#aBhn(:Bm%39ZXfh[a" x="-501" y="275"><mutation name="blinke"><arg name="LED"></arg><arg name="Intervall in ms"></arg><arg name="Anzahl"></arg></mutation><value name="ARG0"><block type="led\_pin" id="whsXNfh-lIpAWK{\*)yyR"><field name="LED">LED1</field></block></value><value name="ARG1"><block type="math\_number" id="=q/em2+pMe7k.anXFg0#"><field name="NUM">50</field></block></value><value name="ARG2"><block type="math\_number" id=";`oMd\*sQd)RzhN`|K\_R2"><field name="NUM">10</field></block></value></block><block type="basic\_comment" id=":MP#z(KgDwd`ANPYm^A0" x="-1156" y="347"><field name="COMMENT">Hinweis: Der Korrekturfaktor soll nicht grösser als 1 sein</field></block><block type="basic\_comment" id="Y/%+\*oQh84;{RYh4B(M#" x="-1161" y="459"><field name="COMMENT">\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*Unterprogramme für Fahrbefehle: nicht verändern oder löschen\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*Entfalte diese Blöcke mit Rechtsklick\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*</field></block><block type="procedures\_defnoreturn" id="B\_Djb,XT!DZg^~PzkcLj" collapsed="true" x="-508" y="504"><mutation><arg name="Tempo in %" varid="s4FBJ~ulwwAj1J|RD1|@"></arg></mutation><field name="NAME">fahre immer gerade, bis ein anderer Fahrbefehl kommt</field><statement name="STACK"><block type="motor\_write\_percentage" id="CVgdsF\_Ciz2#cSa1Uzkr"><value name="MOTOR"><block type="motor\_pin" id="fxi0wOX+xO0pLjR2Um4C"><field name="MOTOR">MOTOR1</field></block></value><value name="PERCENTAGE"><block type="math\_arithmetic" id="4sXfoCfhnC(ydw4TBM@@"><field name="OP">MULTIPLY</field><value name="A"><block type="variables\_get" id="Zc}Ba3k4rN]c44=t/$52"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value><value name="B"><block type="variables\_get" id="w\*\_UOiM8M\_uZkC7HNM7b"><field name="VAR" id="5MT4jvb3P0}5#GS.D,87">Korrektur M1</field></block></value></block></value><next><block type="motor\_write\_percentage" id="\_[vZA74\*R~$5vB~.B{sw"><value name="MOTOR"><block type="motor\_pin" id="=X\*8FmY]Iffj+CPn)xt."><field name="MOTOR">MOTOR2</field></block></value><value name="PERCENTAGE"><block type="math\_arithmetic" id="Yt3k/a{3aSZSt6v5gEi!"><field name="OP">MULTIPLY</field><value name="A"><block type="variables\_get" id="!T1Y;Ym~c\*iG`0BjHDCH"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value><value name="B"><block type="variables\_get" id=":]Y8VlHDYWg}0#.k\*i7n"><field name="VAR" id="HJYdxPCN]:ZCMUgos.h8">Korrektur M2</field></block></value></block></value></block></next></block></statement></block><block type="procedures\_defnoreturn" id="7idn+zmBV^05K)?dbrX2" collapsed="true" x="-507" y="549"><mutation><arg name="Zeit in ms" varid="\*:3e.esi^B`J%$5)X12H"></arg><arg name="Tempo in %" varid="s4FBJ~ulwwAj1J|RD1|@"></arg></mutation><field name="NAME">fahre gerade</field><statement name="STACK"><block type="motor\_write\_percentage" id="CX9lDgiJue@Wp%^M:8Y\_"><value name="MOTOR"><block type="motor\_pin" id="C2kSMb#UFwi:A-ycmz-$"><field name="MOTOR">MOTOR1</field></block></value><value name="PERCENTAGE"><block type="math\_arithmetic" id="|KjW,\*;bXO}e-]tbAwLu"><field name="OP">MULTIPLY</field><value name="A"><block type="variables\_get" id="AL^NrcuqJ9jn^+:.^64l"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value><value name="B"><block type="variables\_get" id="g.4j{{Yw%YzRS@2.RR@q"><field name="VAR" id="5MT4jvb3P0}5#GS.D,87">Korrektur M1</field></block></value></block></value><next><block type="motor\_write\_percentage" id="`\*9P$I8h7l7unf;uuDUY"><value name="MOTOR"><block type="motor\_pin" id="NgfnW}QwW/Sub{E{drVB"><field name="MOTOR">MOTOR2</field></block></value><value name="PERCENTAGE"><block type="math\_arithmetic" id="O8u6QjR\*T6/s;`6p@QJg"><field name="OP">MULTIPLY</field><value name="A"><block type="variables\_get" id="0$J(kR\_T+NlL-Zx`.H\_m"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value><value name="B"><block type="variables\_get" id="-Y{5|/R]n2#\_ZiiG=ukk"><field name="VAR" id="HJYdxPCN]:ZCMUgos.h8">Korrektur M2</field></block></value></block></value><next><block type="flow\_delay" id="$UEwm}\*UK,)O^n3[i+uI"><value name="DELAY"><block type="variables\_get" id="8cp[Ha9+)6(45R8Ea94,"><field name="VAR" id="\*:3e.esi^B`J%$5)X12H">Zeit in ms</field></block></value></block></next></block></next></block></statement></block><block type="procedures\_defnoreturn" id="b$ZY,afDLca(n96G6dI/" collapsed="true" x="-507" y="590"><mutation><arg name="Zeit in ms" varid="\*:3e.esi^B`J%$5)X12H"></arg><arg name="Tempo in %" varid="s4FBJ~ulwwAj1J|RD1|@"></arg></mutation><field name="NAME">drehe rechts</field><statement name="STACK"><block type="motor\_write\_percentage" id="SC3Vb^~=}0G^Vf(W]0Ut"><value name="MOTOR"><block type="motor\_pin" id="O!N8lS^4K.v=zr#l(7\_?"><field name="MOTOR">MOTOR1</field></block></value><value name="PERCENTAGE"><block type="variables\_get" id="({oJFj@/Un`20Vq[/Nu9"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value><next><block type="motor\_write\_percentage" id="JX0cn1WV)iib(C#d2r\*+"><value name="MOTOR"><block type="motor\_pin" id="bEM[LV6.O\*JA,#(2@eAe"><field name="MOTOR">MOTOR2</field></block></value><value name="PERCENTAGE"><block type="math\_single\_basic" id="I8?+tyfP,,S=U2(J4f8)"><field name="OP">NEG</field><value name="NUM"><block type="variables\_get" id="o]9\*O`O0)xdqIA8pk]!{"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value></block></value><next><block type="flow\_delay" id="}|w]BVgUtOIS~t:hvsM{"><value name="DELAY"><block type="variables\_get" id="Yom)S?%MT|X/9$j\_.9ZX"><field name="VAR" id="\*:3e.esi^B`J%$5)X12H">Zeit in ms</field></block></value></block></next></block></next></block></statement></block><block type="procedures\_defnoreturn" id="#;\_5#6Swhgm#)6$rs/`7" collapsed="true" x="-507" y="633"><mutation><arg name="Zeit in ms" varid="\*:3e.esi^B`J%$5)X12H"></arg><arg name="Tempo in %" varid="s4FBJ~ulwwAj1J|RD1|@"></arg></mutation><field name="NAME">drehe links</field><statement name="STACK"><block type="motor\_write\_percentage" id="lm\*;)+^AODwf;u6NRo6T"><value name="MOTOR"><block type="motor\_pin" id="~Aw#)pqDmD#W[{mM=b?l"><field name="MOTOR">MOTOR1</field></block></value><value name="PERCENTAGE"><block type="math\_single\_basic" id="X+%.H2wRzBaugs8Tg@BZ"><field name="OP">NEG</field><value name="NUM"><block type="variables\_get" id="/NYNXzSb\_uYJ,lImtmjy"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value></block></value><next><block type="motor\_write\_percentage" id="Jx}1%or79[7115hz.W5t"><value name="MOTOR"><block type="motor\_pin" id="1w-f|QjK}dA$?UG]l9\_{"><field name="MOTOR">MOTOR2</field></block></value><value name="PERCENTAGE"><block type="variables\_get" id="uLu.#62J{x:~Rq1ZM3N`"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value><next><block type="flow\_delay" id="!|dN{0\*B-IuAiY3u/ydB"><value name="DELAY"><block type="variables\_get" id="4@d=mE/zr{b~[Pm#d65j"><field name="VAR" id="\*:3e.esi^B`J%$5)X12H">Zeit in ms</field></block></value></block></next></block></next></block></statement></block><block type="procedures\_defnoreturn" id="kB`@8{W4N]8a62og=X,/" collapsed="true" x="-508" y="673"><mutation><arg name="Start-Tempo" varid="LxkGe)=JaZ:.FWq%8/{%"></arg><arg name="End-Tempo" varid="QmpV861a}-ED`kw\_!OUj"></arg><arg name="Zeit in ms" varid="\*:3e.esi^B`J%$5)X12H"></arg></mutation><field name="NAME">beschleunige gerade</field><statement name="STACK"><block type="flow\_for" id="K7zxz\_2AdWC:ro~hE3UG"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field><value name="FROM"><block type="variables\_get" id="EEJ.wGG?Rf(]T3G.Q$-Y"><field name="VAR" id="LxkGe)=JaZ:.FWq%8/{%">Start-Tempo</field></block></value><value name="TO"><block type="variables\_get" id="Yh+)1DFZH~t3~$7b|+~V"><field name="VAR" id="QmpV861a}-ED`kw\_!OUj">End-Tempo</field></block></value><value name="BY"><block type="math\_arithmetic" id="w=)4r,$8s)w0i5Z9]slP"><field name="OP">DIVIDE</field><value name="A"><block type="math\_single\_basic" id="J}GFmoMcj2jrV1n}34r@"><field name="OP">ABS</field><value name="NUM"><block type="math\_arithmetic" id="eAHQK#478Zr04L#%zXVX"><field name="OP">MINUS</field><value name="A"><block type="variables\_get" id="lGKl.z?bO3QA`3?|Vxpf"><field name="VAR" id="LxkGe)=JaZ:.FWq%8/{%">Start-Tempo</field></block></value><value name="B"><block type="variables\_get" id="E9SalBeRLNa6]tv)-12f"><field name="VAR" id="QmpV861a}-ED`kw\_!OUj">End-Tempo</field></block></value></block></value></block></value><value name="B"><block type="variables\_get" id="`kEE9ROpCT![N%}p6;u8"><field name="VAR" id="\*:3e.esi^B`J%$5)X12H">Zeit in ms</field></block></value></block></value><statement name="DO"><block type="motor\_write\_percentage" id="aO6!Re;~6y,48$4i`GJ^"><value name="MOTOR"><block type="motor\_pin" id="8LgGxImN)|1r8a[IXGI1"><field name="MOTOR">MOTOR1</field></block></value><value name="PERCENTAGE"><block type="math\_arithmetic" id="#}=-G#;oVZ=.e61^9bt%"><field name="OP">MULTIPLY</field><value name="A"><block type="variables\_get" id="z5,:.g90Hf{sh(KZw$Km"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value><value name="B"><block type="variables\_get" id="HHDgjtii1nJ%W.JtfV25"><field name="VAR" id="5MT4jvb3P0}5#GS.D,87">Korrektur M1</field></block></value></block></value><next><block type="motor\_write\_percentage" id="O=0KkQ]6fGYHQ)2@Pz}="><value name="MOTOR"><block type="motor\_pin" id="~\_}-G3=@D5^X:%RKG7u."><field name="MOTOR">MOTOR2</field></block></value><value name="PERCENTAGE"><block type="math\_arithmetic" id="K2{7\*QDhtAn{2}-WD/%d"><field name="OP">MULTIPLY</field><value name="A"><block type="variables\_get" id="@vp;6/WSb~=i^MhS=S-r"><field name="VAR" id="s4FBJ~ulwwAj1J|RD1|@">Tempo in %</field></block></value><value name="B"><block type="variables\_get" id="I/JOS)4%CyQan/3:iUAf"><field name="VAR" id="HJYdxPCN]:ZCMUgos.h8">Korrektur M2</field></block></value></block></value><next><block type="flow\_delay" id=";lzYQKjlTTZqDc/\_4:^m"><value name="DELAY"><block type="math\_number" id="z3s(n37Bs{Hy/5[9LV!A"><field name="NUM">1</field></block></value></block></next></block></next></block></statement></block></statement></block><block type="procedures\_defnoreturn" id="\*2`6\*YJKnt%=!hvULK)i" collapsed="true" x="-505" y="718"><mutation><arg name="Zeit in ms" varid="\*:3e.esi^B`J%$5)X12H"></arg></mutation><field name="NAME">stoppe</field><statement name="STACK"><block type="motor\_write\_percentage" id="E|],,BqSrLd9@{yC;9Tl"><value name="MOTOR"><block type="motor\_pin" id="WqAs2=rW5usmc%/1YGCP"><field name="MOTOR">MOTOR1</field></block></value><value name="PERCENTAGE"><block type="math\_number" id="#Uq}-VfY@VR(AgmJUbka"><field name="NUM">0</field></block></value><next><block type="motor\_write\_percentage" id="D5Vx`5TgSaKxMtd\*=;c6"><value name="MOTOR"><block type="motor\_pin" id="#q1Mj6\*B0z4nQpm53QrG"><field name="MOTOR">MOTOR2</field></block></value><value name="PERCENTAGE"><block type="math\_number" id="9`Jq(CJP-z8v@RbaiLpX"><field name="NUM">0</field></block></value><next><block type="flow\_delay" id="D;Oe@ky+Qf:ab7[b^qC%"><value name="DELAY"><block type="variables\_get" id="\*7c5;7=kM8(\_T\_.4J1Xz"><field name="VAR" id="\*:3e.esi^B`J%$5)X12H">Zeit in ms</field></block></value></block></next></block></next></block></statement></block><block type="procedures\_defnoreturn" id="D?8m~{UZEw,gRWJ=lyrt" collapsed="true" x="-504" y="764"><field name="NAME">stoppe bis Sensor 1 oder 2 berührt werden</field><statement name="STACK"><block type="flow\_until" id="LK(cABcMVespL,%xl[I;"><value name="CONDITION"><block type="logic\_operation" id="V6,O|T(Mm+Pa=5|GSI;O"><field name="OP">OR</field><value name="A"><block type="sensor\_test\_state" id="k$)Xq$(Th.l(np;6l%(W"><field name="MODE">STANDARD</field><value name="SENSOR"><block type="sensor\_pin" id="4:2cV=t#v|y\*ns:57|pk"><field name="SENSOR">SENSOR1</field></block></value><value name="STATE"><block type="basic\_digital\_state" id="^Z!2?Q2fU{W#\*2QjXb|B"><field name="STATE">LOW</field></block></value></block></value><value name="B"><block type="sensor\_test\_state" id="VN9EtrJK+|Y,~cl([\_?A"><field name="MODE">STANDARD</field><value name="SENSOR"><block type="sensor\_pin" id="90K\_jtZ(.ed,2iG%|X~!"><field name="SENSOR">SENSOR2</field></block></value><value name="STATE"><block type="basic\_digital\_state" id="CoMqFe6[PDLh.Hh`Q{yH"><field name="STATE">LOW</field></block></value></block></value></block></value><statement name="DO"><block type="motor\_write\_percentage" id="8hy}9/~4vU]~)O%)iI44"><value name="MOTOR"><block type="motor\_pin" id="fD%R\*49Zq3eeRUj.dI4{"><field name="MOTOR">MOTOR1</field></block></value><value name="PERCENTAGE"><block type="math\_number" id="+DlNfo+sED)Zf]/dbhO)"><field name="NUM">0</field></block></value><next><block type="motor\_write\_percentage" id=":C:t@)w5[q.\*7bQ^,D\*{"><value name="MOTOR"><block type="motor\_pin" id="N!dR[Rpyg}t8U18N9`b9"><field name="MOTOR">MOTOR2</field></block></value><value name="PERCENTAGE"><block type="math\_number" id="Mxo-NI/L`L|\*K@L\_MT3}"><field name="NUM">0</field></block></value></block></next></block></statement></block></statement></block><block type="procedures\_defnoreturn" id="teqdL;Xne}3\_$#5acQG1" collapsed="true" x="-505" y="831"><mutation><arg name="LED" varid="lO0ZYE\*d3-TBXT4=/F%w"></arg><arg name="Intervall in ms" varid="0z{{\*X:B1%h{p$#~9jog"></arg><arg name="Anzahl" varid="?~`j6li~gz]E9ASa.KQP"></arg></mutation><field name="NAME">blinke</field><statement name="STACK"><block type="flow\_repeat" id="84;0;QCkVHG[hWb6S;jk"><value name="REPEATS"><block type="variables\_get" id="[(%4+5h?#NVufzwMm=PU"><field name="VAR" id="?~`j6li~gz]E9ASa.KQP">Anzahl</field></block></value><statement name="DO"><block type="led\_write\_state" id="Q#r$V/4}goLh4JCARX2t"><value name="LED"><block type="variables\_get" id="Ie(zgrcCcG@akugpkI0X"><field name="VAR" id="lO0ZYE\*d3-TBXT4=/F%w">LED</field></block></value><value name="VALUE"><block type="basic\_digital\_state" id="9UbkEDc8XOV-=Gp:\_sv2"><field name="STATE">LOW</field></block></value><next><block type="flow\_delay" id="22HE}R^VvW-2eQDVm4rJ"><value name="DELAY"><block type="variables\_get" id="UFVbmq{CWS\_-A!Cl!\*ir"><field name="VAR" id="0z{{\*X:B1%h{p$#~9jog">Intervall in ms</field></block></value><next><block type="led\_write\_state" id="sax\*9,CvXy\*]nL~T?12;"><value name="LED"><block type="variables\_get" id="!qIT15TscM\_85X+q#EeE"><field name="VAR" id="lO0ZYE\*d3-TBXT4=/F%w">LED</field></block></value><value name="VALUE"><block type="basic\_digital\_state" id="uSl\_cJOh~$TP,|tPH]ja"><field name="STATE">HIGH</field></block></value><next><block type="flow\_delay" id=")~B2viE[QaJ,l`.SaQy:"><value name="DELAY"><block type="variables\_get" id="DN~]AhE``r`IlVz/A=|}"><field name="VAR" id="0z{{\*X:B1%h{p$#~9jog">Intervall in ms</field></block></value></block></next></block></next></block></next></block></statement></block></statement></block><block type="procedures\_defreturn" id="1{95fOK|YQj$):Ye?tzx" collapsed="true" x="-505" y="871"><field name="NAME">Gemessene Distanz in cm mit Ultraschallsensor an S3</field><statement name="STACK"><block type="led\_write\_state" id="D.Aw@M=~$.grAnuObBbh"><value name="LED"><block type="led\_pin" id="/?Hx;.FZ0Z:~,P`Y\_Iy+"><field name="LED">LED3</field></block></value><value name="VALUE"><block type="basic\_digital\_state" id="EGCbx{pK#/c0)bpQ1S$:"><field name="STATE">LOW</field></block></value><next><block type="flow\_delay\_micro" id="~vi$Q8|t,ieh9x9{,-}j"><value name="DELAY\_MICRO"><block type="math\_number" id="0F!T(vR({+A.e4t)+)eq"><field name="NUM">5</field></block></value><next><block type="led\_write\_state" id="a~{7Z\*qj}GBpctRT.n[Y"><value name="LED"><block type="led\_pin" id="etDp;!3hx\*ZAv(vgedP?"><field name="LED">LED3</field></block></value><value name="VALUE"><block type="basic\_digital\_state" id="yCl~sepJMya+Vn})\_+LN"><field name="STATE">HIGH</field></block></value><next><block type="flow\_delay\_micro" id="(7IH(q}Ufp3QMa]A#\_hx"><value name="DELAY\_MICRO"><block type="math\_number" id="d~5}kTDbC:~nW9weO=[m"><field name="NUM">10</field></block></value><next><block type="led\_write\_state" id="4;ge?pcgEgn;zTr%4\*|b"><value name="LED"><block type="led\_pin" id="rr[C%~Z~,d}t(rKdpVNO"><field name="LED">LED3</field></block></value><value name="VALUE"><block type="basic\_digital\_state" id="E9vmv$q}|S@0eWRLa6v."><field name="STATE">LOW</field></block></value><next><block type="flow\_while" id="J46#ClY#8iAC|d9sd[D7"><value name="CONDITION"><block type="logic\_compare" id="2$H]yr/vzffF7\_\*NaCF`"><field name="OP">EQ</field><value name="A"><block type="sensor\_read\_state" id="QS.D0VHOBqgW?XtRvDhV"><value name="SENSOR"><block type="sensor\_pin" id="FIKu6\*CWMd%^n@%;^KPq"><field name="SENSOR">SENSOR3</field></block></value></block></value><value name="B"><block type="basic\_digital\_state" id="-|ZQEDJ,%tpzxHWoszw\_"><field name="STATE">LOW</field></block></value></block></value><next><block type="variables\_set" id="8H6mMsf:00(JgN8#9~kY"><field name="VAR" id="Gt#^=(OVC9s1jWO6hUFu">Zeitstempel</field><value name="VALUE"><block type="flow\_micro" id="uFTPzVQjA.:7?574Dz+S"></block></value><next><block type="flow\_while" id="0+JWcX7${c/V1agz~{~~"><value name="CONDITION"><block type="logic\_compare" id="O7#zdEPJy/Z$|BTFpZnu"><field name="OP">EQ</field><value name="A"><block type="sensor\_read\_state" id="p8::;:/2c9C72N:/Z+q("><value name="SENSOR"><block type="sensor\_pin" id="w-[7Bh]ve|c1!{$T94/0"><field name="SENSOR">SENSOR3</field></block></value></block></value><value name="B"><block type="basic\_digital\_state" id="zKa(1}|0Z-piFkA$e)7X"><field name="STATE">HIGH</field></block></value></block></value><next><block type="variables\_set" id=")+y.m%pPfDM$GPWR/5`}"><field name="VAR" id=".gklvtf4@5gvI|=mU7D/">Verstrichene Zeit</field><value name="VALUE"><block type="math\_arithmetic" id="|ZG9t6SFEv9Hk^Bwwk6["><field name="OP">MINUS</field><value name="A"><block type="flow\_micro" id="dP6IOW}qTd@+^-0}R1Ym"></block></value><value name="B"><block type="variables\_get" id="xS2=qGUJ;~\_DUY:{-P[G"><field name="VAR" id="Gt#^=(OVC9s1jWO6hUFu">Zeitstempel</field></block></value></block></value><next><block type="variables\_set" id="tz1MO],0y\*wAVS)|\*)Y?"><field name="VAR" id="|~,OsB~H~X)([2gt$CLf">Distanz in cm</field><value name="VALUE"><block type="math\_arithmetic" id=")[DkL;,Uxl/SZD;Hn}7v"><field name="OP">MULTIPLY</field><value name="A"><block type="variables\_get" id="#uxi(=)]|Ai)(s:+aqA5"><field name="VAR" id=".gklvtf4@5gvI|=mU7D/">Verstrichene Zeit</field></block></value><value name="B"><block type="math\_number" id="r?Kb;9IssvYq(JJ^Ilt="><field name="NUM">0.0175</field></block></value></block></value></block></next></block></next></block></next></block></next></block></next></block></next></block></next></block></next></block></next></block></statement><value name="RETURN"><block type="variables\_get" id="3bEb2ZLsqp!xXU!g}7N/"><field name="VAR" id="|~,OsB~H~X)([2gt$CLf">Distanz in cm</field></block></value></block></xml>