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code><translations></translations><inputs><input
type="%txt">group_name</input></inputs><script><block
s="doDeclareVariables"><list><l>output</l></list></block><block
s="doSetVar"><l>output</l><block s="reportURL"><block
s="reportJoinWords"><list><custom-block s="$robot robot URL"></
custom-block><l>/motors/</l><block var="alias"/></list></block></
block></block><block s="doIfElse"><block s="reportEquals"><block
var="output"/><l></l></block><script><custom-block s="$robot popup
%txt"><block s="reportJoinWords"><list><l>Group &lt; </l><block
var="alias"/><l> &gt; is not in the aivable groups of your robot :
</l><custom-block s="combine with %repRing items of %l"><block
s="reifyReporter"><autolambda><custom-block s="join words
%mult%txt"><list><l></l><l></l></list></custom-block></
autolambda><list></list></block><custom-block s="$robot all motors
groups"></custom-block></custom-block></list></block></custom-
block><block s="doReport"><l></l></block></script><script><block
s="doReport"><block s="reportTextSplit"><block var="output"/><l></
l></block></block></script></block></script></block-
definition><block-definition s="$robot all motors" type="reporter"
category="sensing"><comment x="0" y="0" w="90"
collapsed="false">Return a list of all available motors</
comment><header></header><code></code><translations></
translations><inputs></inputs><script><block s="doReport"><custom-
block s="$robot motors in group %txt"><l>motors</l></custom-block></
block></script></block-definition><block-definition s="if
%&apos;test&apos; then %&apos;true&apos; else %&apos;false&apos;"
type="reporter" category="control"><header></header><code></
code><translations></translations><inputs><input type="%b"></
input><input type="%anyUE"></input><input type="%anyUE"></input></
inputs><script><block s="doIfElse"><block var="test"/><script><block
s="doReport"><block s="evaluate"><block var="true"/><list></list></
```

```
block></block></script><script><block s="doReport"><block
s="evaluate"><block var="false"/><list></list></block></block></
script></block></script></block-definition><block-definition
s="$robot get &apos;register&apos; of motor(s) &apos;motors&apos;";
type="reporter" category="sensing"><comment x="0" y="0"
w="230.00000099999988" collapsed="false">Get a defined
<lt;register> <lt;value> of one motor.&#xD;Example of some
registers : torque_limit, angle_limit, present_temperature,
present_position...&#xD;For more informations about registers, look
at the online documentation : http://\$robot-project.github.io/pypot/
&#xD;</comment><header></header><code></code><translations></
translations><inputs><input
type="%s">present_position<options>position=present_position&#xD;spe
ed=present_speed&#xD;load
(force)=present_load&#xD;temperature=present_temperature&#xD;voltage
=present_voltage</options></input><input type="%s">motor_name</
input></inputs><script><block
s="doDeclareVariables"><list><l>output</l><l>complete motor list</
l></list></block><block s="doSetVar"><l>complete motor list</
l><custom-block s="$robot all motors"></custom-block></block><block
s="doIf"><block s="reportNot"><block s="reportIsA"><block
var="motors"/><l><option>list</option></l></block></
block><script><block s="doIfElse"><block s="report0r"><block
s="reportIsIdentical"><block var="motors"/><l>all</l></block><block
s="reportIsIdentical"><block var="motors"/><l></l></block></
block><script><block s="doSetVar"><l>motors</l><custom-block
s="$robot all motors"></custom-block></block></script><script><block
s="doSetVar"><l>motors</l><block s="reportTextSplit"><block
var="motors"/><l><option>whitespace</option></l></block></block></
script></block></script></block><custom-block s="for each %upvar of
%l %cs"><l>m</l><block var="motors"/><script><block s="doIf"><block
s="reportNot"><block s="reportListContainsItem"><block var="complete
motor list"/><block var="m"/></block></block><script><custom-block
s="$robot popup %txt"><block s="reportJoinWords"><list><l>Motor <lt;
</l><block var="m"/><l> &gt; is not in the available motors of your
robot : </l><custom-block s="combine with %repRing items of
%l"><block s="reifyReporter"><autolambda><custom-block s="join words
%mult%txt"><list><l></l><l></l></list></custom-block></
autolambda><list></list></block><block var="complete motor list"/></
custom-block></list></block></custom-block><block s="doReport"><l></
l></block></script></block></script></custom-block><block
s="doReport"><block s="reportTextSplit"><block s="reportURL"><block
s="reportJoinWords"><list><custom-block s="$robot robot URL"></
custom-block><l>/motors/</l><custom-block s="combine with %repRing
items of %l"><block s="reifyReporter"><autolambda><block
s="reportJoinWords"><list><block var="#1"/><l>;</l><block var="#2"/
></list></block></autolambda><list><l>#1</l><l>#2</l></list></
block><block var="motors"/></custom-block><l>/get/</l><block
var="register"/></list></block></block><l>;</l></block></block></
script></block-definition><block-definition s="$robot robot URL"
type="reporter" category="sensing"><comment x="0" y="0" w="117"
collapsed="false">For internal use only</comment><header></
header><code></code><translations></translations><inputs></
inputs><script><block s="doReport"><block
```

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s="reportJoinWords"><list><block var="host"/><l>:</l><block
var="port"/></list></block></block></script></block-
definition><block-definition s="$robot set motor(s)
'motor' compliant;" type="command"
category="control"><comment x="0" y="0" w="230.00000099999988"
collapsed="false">Compliance property make motors actively become
soft and movable.&#xD;You need to activate the compliance if you
want to record a movement by demonstration.&#xD;&#xD;The motor(s)
input can accept :&#xD;- string of a motor name&#xD;- string of many
motors separed with spaces&#xD;- a Snap! list of motors like the
reporter block &quot;$robot all motors&quot;</comment><header></
header><code></code><translations></translations><inputs><input
type="%s">motor_name</input><input type="%txt"
readonly="true">compliant<options>compliant&#xD;stiff</options></
input></inputs><script><block s="doDeclareVariables"><list><l>comp</
l></list></block><block s="doSetVar"><l>comp</l><custom-block s="if
%b then %anyUE else %anyUE"><block s="reportOr"><block
s="reportEquals"><block var="compliant"/><l>compliant</l></
block><block var="compliant"/></block><l>1</l><l>0</l></custom-
block></block><custom-block s="$robot set %txt of motor(s) %s to
%s"><l>compliant</l><block var="motor"/><block var="comp"/></custom-
block></script></block-definition><block-definition s="$robot set
position(s) 'position' of motor(s) 'motors' in
'duration' seconds | wait ? 'wait'"
type="command" category="control"><comment x="0" y="0"
w="230.00000099999988" collapsed="false">set motor to the desired
position (angle) in the desired time.&#xD;&#xD;The motor(s) input
can accept :&#xD;- string of a motor name&#xD;- string of many
motors separed with spaces&#xD;- a Snap! list of motors like the
reporter block &quot;$robot all motors&quot;</comment><header></
header><code></code><translations></translations><inputs><input
type="%n">0</input><input type="%s">motor_name</input><input
type="%n">2</input><input type="%boolUE"></input></
inputs><script><block s="doDeclareVariables"><list><l>output</
l><l>complete motor list</l><l>i</l><l>mot_pos</l><l>query_URL</
l></list></block><block s="doSetVar"><l>mot_pos</l><block
s="reportNewList"><list></list></block></block><block
s="doSetVar"><l>i</l><l>1</l></block><block s="doSetVar"><l>complete
motor list</l><custom-block s="$robot all motors"></custom-block></
block><block s="doIf"><block s="reportNot"><block
s="reportIsA"><block var="motors"/><l><option>list</option></l></
block></block><script><block s="doIfElse"><block
s="reportIsIdentical"><block var="motors"/><l></l></
block><script><block s="doSetVar"><l>motors</l><custom-block
s="$robot all motors"></custom-block></block></script><script><block
s="doSetVar"><l>motors</l><block s="reportTextSplit"><block
var="motors"/><l><option>whitespace</option></l></block></block></
script></block></script></block><custom-block s="for each %upvar of
%l %cs"><l>m</l><block var="motors"/><script><block
s="doIfElse"><block s="reportNot"><block
s="reportListContainsItem"><block var="complete motor list"/><block
var="m"/></block></block><script><custom-block s="$robot popup
%txt"><block s="reportJoinWords"><list><l>Motor </l><block var="m"/
><l> is not in the aivaible motors of your robot : </l><custom-

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block s="combine with %repRing items of %l"><block
s="reifyReporter"><autolambda><custom-block s="join words
%mult%txt"><list><l></l><l></l></list></custom-block></
autolambda><list></list></block><block var="complete motor list"/></
custom-block></list></block></custom-block><block s="doReport"><l></
l></block></script><script><block s="doIfElse"><block
s="reportIsA"><block var="position"/><l><option>list</option></l></
block><script><block s="doAddToList"><block
s="reportJoinWords"><list><block var="m"/><l>:</l><block
s="reportListItem"><block var="i"/><block var="position"/></block></
list></block><block var="mot_pos"/></block></script><script><block
s="doAddToList"><block s="reportJoinWords"><list><block var="m"/
><l>:</l><block var="position"/></list></block><block var="mot_pos"/
></block></script></block></script></block><block
s="doChangeVar"><l>i</l><l>1</l></block></script></custom-
block><block s="doSetVar"><l>query_URL</l><block
s="reportURL"><block s="reportJoinWords"><list><custom-block
s="$robot robot URL"></custom-block><l>/motors/set/goto/</l><block
s="reportJoinWords"><list><custom-block s="combine with %repRing
items of %l"><block s="reifyReporter"><autolambda><block
s="reportJoinWords"><list><block var="#1"/><l>:</l><block
var="duration"/><l>;</l><block var="#2"/></list></block></
autolambda><list><l>#1</l><l>#2</l></list></block><block
var="mot_pos"/></custom-block><l>:</l><block var="duration"/></
list></block></list></block></block></block><block
s="doIfElse"><block s="evaluate"><block var="wait"/><list></list></
block><script><block s="doRun"><block
s="reifyReporter"><autolambda><block var="query_URL"/></
autolambda><list></list></block><list></list></block><block
s="doWait"><block var="duration"/></block></script><script><block
s="doReport"><block var="query_URL"/></block></script></block></
script></block-definition><block-definition s="$robot set
%&apos;register&apos; of motor(s) %&apos;motors&apos; to
%&apos;value&apos;" type="command" category="control"><comment x="0"
y="0" w="230.00000099999988" collapsed="false">Set a defined
<value> to a defined <register> of one or many
motors.&#xD;Example of some registers : torque_limit, angle_limit,
safe_compliant, compliant...&#xD;For more informations about
registers, look at the online documentation : http://$robot-
project.github.io/pypot/&#xD;&#xD;The motor(s) input can
accept :&#xD;- string of a motor name&#xD;- string of many motors
separed with spaces&#xD;- a Snap! list of motors like the reporter
block &quot;$robot all motors&quot;</comment><header></
header><code></code><translations></translations><inputs><input
type="%txt"><options>position=goal_position&#xD;speed=moving_speed&#
xD;max torque(%)=torque_limit&#xD;compliance(True or
False)=compliant</options></input><input type="%s">motor_name</
input><input type="%s">value(s)</input></inputs><script><block
s="doDeclareVariables"><list><l>output</l><l>complete motor list</
l></list></block><block s="doSetVar"><l>complete motor list</
l><custom-block s="$robot all motors"></custom-block></block><block
s="doIf"><block s="reportNot"><block s="reportIsA"><block
var="motors"/><l><option>list</option></l></block></
block><script><block s="doIfElse"><block

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s="reportIsIdentical"><block var="motors"/><l>all</l></
block><script><block s="doSetVar"><l>motors</l><custom-block
s="$robot all motors"></custom-block></block></script><script><block
s="doSetVar"><l>motors</l><block s="reportTextSplit"><block
var="motors"/><l><option>whitespace</option></l></block></block></
script></block></script></block><custom-block s="for each %upvar of
%l %cs"><l>m</l><block var="motors"/><script><block s="doIf"><block
s="reportNot"><block s="reportListContainsItem"><block var="complete
motor list"/><block var="m"/></block></block><script><custom-block
s="$robot popup %txt"><block s="reportJoinWords"><list><l>Motor &lt;
</l><block var="m"/><l> &gt; is not in the aivaible motors of your
robot : </l><custom-block s="combine with %repRing items of
%l"><block s="reifyReporter"><autolambda><custom-block s="join words
%mult%txt"><list><l></l><l></l></list></custom-block></
autolambda><list></list></block><block var="complete motor list"/></
custom-block></list></block></custom-block><block s="doReport"><l></
l></block></script></block></script></custom-block><block
s="doReport"><block s="reportURL"><block
s="reportJoinWords"><list><custom-block s="$robot robot URL"></
custom-block><l>/motors/set/registers/</l><block
s="reportJoinWords"><list><custom-block s="combine with %repRing
items of %l"><block s="reifyReporter"><autolambda><block
s="reportJoinWords"><list><block var="#1"/><l>:</l><block
var="register"/><l>:</l><block var="value"/><l>;</l><block var="#2"/
></list></block></autolambda><list><l>#1</l><l>#2</l></list></
block><block var="motors"/></custom-block><l>:</l><block
var="register"/><l>:</l><block var="value"/></list></block></list></
block></block></block></script></block-definition><block-definition
s="$robot get &apos;running&apos; behaviours" type="reporter"
category="sensing"><header></header><code></code><translations></
translations><inputs><input type="%s"
readonly="true">all<options>all&#xD;running</options></input></
inputs><script><block s="doIfElse"><block
s="reportIsIdentical"><block var="running"/><l>running</l></
block><script><block s="doReport"><block s="reportTextSplit"><block
s="reportURL"><block s="reportJoinWords"><list><custom-block
s="$robot robot URL"></custom-block><l>/primitives/</l><l>running</
l></list></block></block><l>/</l></block></block></
script><script><block s="doReport"><block s="reportTextSplit"><block
s="reportURL"><block s="reportJoinWords"><list><custom-block
s="$robot robot URL"></custom-block><l>/primitives</l><l></l></
list></block></block><l>/</l></block></block></script></block></
script></block-definition><block-definition s="empty?
&apos;data&apos;" type="predicate" category="lists"><header></
header><code></code><translations></translations><inputs><input
type="%l"></input></inputs><script><block s="doReport"><block
s="reportEquals"><block var="data"/><block
s="reportNewList"><list></list></block></block></block></script></
block-definition><block-definition s="combine with
&apos;function&apos; items of &apos;data&apos;" type="reporter"
category="lists"><header></header><code></code><translations></
translations><inputs><input type="%repRing"></input><input
type="%l"></input></inputs><script><block s="doWarp"><script><block
s="doIf"><custom-block s="empty? %l"><block s="reportCDR"><block
```

```
var="data"/></block></custom-block><script><block
s="doReport"><block s="reportListItem"><l>1</l><block var="data"/></
block></block></script></block><block s="doReport"><block
s="evaluate"><block var="function"/><list><block
s="reportListItem"><l>1</l><block var="data"/></block><custom-block
s="combine with %repRing items of %l"><block var="function"/><block
s="reportCDR"><block var="data"/></block></custom-block></list></
block></block></script></block></script></block-definition><block-
definition s="join words %&apos;words&apos;" type="reporter"
category="operators"><header></header><code></code><translations></
translations><inputs><input type="%mult%txt"></input></
inputs><script><block s="doWarp"><script><block s="doIf"><custom-
block s="empty? %l"><block s="reportCDR"><block var="words"/></
block></custom-block><script><block s="doReport"><block
s="reportListItem"><l>1</l><block var="words"/></block></block></
script></block><block s="doReport"><block
s="reportJoinWords"><list><block s="reportListItem"><l>1</l><block
var="words"/></block><block s="reportJoinWords"><list><l> </l><block
s="evaluate"><block s="reifyReporter"><autolambda><custom-block
s="join words %mult%txt"><block s="reportCDR"><block var="words"/></
block></custom-block></autolambda><list></list></block><list></
list></block></list></block></list></block></script></
block></script></block-definition><block-definition s="for each
%&apos;item&apos; of %&apos;data&apos; %&apos;action&apos;"
type="command" category="lists"><header></header><code></
code><translations></translations><inputs><input type="%upvar"></
input><input type="%l"></input><input type="%cs"></input></
inputs><script><block s="doUntil"><custom-block s="empty? %l"><block
var="data"/></custom-block><script><block s="doSetVar"><l>item</
l><block s="reportListItem"><l>1</l><block var="data"/></block></
block><block s="doRun"><block var="action"/><list><block
s="reportListItem"><l>1</l><block var="data"/></block></list></
block><block s="doSetVar"><l>data</l><block s="reportCDR"><block
var="data"/></block></block></script></block></script></block-
definition><block-definition s="$robot popup %&apos;message&apos;"
type="command" category="other"><header></header><code></
code><translations></translations><inputs><input type="%txt"></
input></inputs><script><block s="doRun"><block
s="reportJSFunction"><list><l>message</l></list><l>alert(message);</
l></block><list><block var="message"/></list></block></script></
block-definition><block-definition s="$robot all motors groups"
type="reporter" category="sensing"><comment x="0" y="0" w="171"
collapsed="false">Return a list of all aliases.&#xD;Alias is a
keyword for representing many motors at once. </comment><header></
header><code></code><translations></translations><inputs></
inputs><script><block s="doReport"><block s="reportTextSplit"><block
s="reportURL"><block s="reportJoinWords"><list><custom-block
s="$robot robot URL"></custom-block><l>/motors/</l><l>alias</l></
list></block></block><l>/</l></block></block></script></block-
definition><block-definition s="$robot test connection"
type="reporter" category="sensing"><header></header><code></
code><translations></translations><inputs></inputs><script><block
s="doIfElse"><custom-block s="ping http:// %s"><custom-block
s="$robot robot URL"></custom-block></custom-block><script><block
```

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s="doReport"><l>Connection ok!</l></block></script><script><block
s="doReport"><l>You may have connection troubles. Check the host
variable</l></block></script></block></script></block-
definition><block-definition s="$robot 'action'
behaviours 'primitive';" type="command"
category="control"><header></header><code></code><translations></
translations><inputs><input type="%txt"
readonly="true">start<options>start&#xD;stop&#xD;pause&#xD;resume</
options></input><input type="%txt"></input></inputs><script><block
s="doDeclareVariables"><list><l>all primitives</l><l>keyword list</
l></list></block><block s="doSetVar"><l>all primitives</l><custom-
block s="$robot get %s behaviours"><l>all</l></custom-block></
block><block s="doSetVar"><l>keyword list</l><block
s="reportNewList"><list><l>start</l><l>stop</l><l>pause</
l><l>resume</l></list></block></block><block s="doIfElse"><block
s="reportNot"><block s="reportListContainsItem"><block var="all
primitives"/><block var="primitive"/></block></
block><script><custom-block s="$robot popup %txt"><block
s="reportJoinWords"><list><l>Primitive &lt; </l><block
var="primitive"/><l> &gt; is not in the aivaible primitives of your
robot : </l><custom-block s="combine with %repRing items of
%l"><block s="reifyReporter"><autolambda><custom-block s="join words
%mult%txt"><list><l></l><l></l></list></custom-block></
autolambda><list></list></block><block var="all primitives"/></
custom-block></list></block></custom-block><block s="doReport"><l></
l></block></script><script><block s="doIfElse"><block
s="reportNot"><block s="reportListContainsItem"><block var="keyword
list"/><block var="action"/></block></block><script><custom-block
s="$robot popup %txt"><block s="reportJoinWords"><list><l>Action
&lt; </l><block var="action"/><l> &gt; is not valid : </l><custom-
block s="combine with %repRing items of %l"><block
s="reifyReporter"><autolambda><custom-block s="join words
%mult%txt"><list><l></l><l></l></list></custom-block></
autolambda><list></list></block><block var="keyword list"/></custom-
block></list></block></custom-block><block s="doReport"><l></l></
block></script><script><block s="doReport"><block
s="reportURL"><block s="reportJoinWords"><list><custom-block
s="$robot robot URL"></custom-block><l>/primitive/</l><block
var="primitive"/><l></l><block var="action"/></list></block></
block></block></script></block></script></block></script></block-
definition><block-definition s="set $robot host to
'hostname'" type="command"
category="variables"><header></header><code></code><translations></
translations><inputs><input type="%s"></input></
inputs><script><block s="doSetVar"><l>host</l><block var="hostname"/
></block><block s="doDeclareVariables"><list><l>tmp_hostname</l></
list></block><block s="doResetTimer"></block><block
s="doUntil"><block s="reportGreaterThan"><block s="getTimer"></
block><l>10</l></block><script><block s="doSetVar"><l>tmp_hostname</
l><block s="reportURL"><block s="reportJoinWords"><list><custom-
block s="$robot robot URL"></custom-block><l>/ip/</l></list></
block></block></block><block s="doIf"><block
s="reportGreaterThan"><block s="reportStringSize"><block
var="tmp_hostname"/></block><l>1</l></block><script><block
```

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s="doSetVar"><l>host</l><block var="tmp_hostname"/></block><block
s="bubble"><custom-block s="$robot test connection"></custom-
block></block><block s="doReport"><l></l></block></script></
block><block s="doWait"><l>0.1</l></block></script></block><custom-
block s="$robot popup %txt"><l>Your robot host is unreachble</l></
custom-block></script></block-definition><block-definition s="ping
http:// %&apos;url&apos;" type="predicate"
category="operators"><header></header><code></code><translations></
translations><inputs><input type="%s"></input></
inputs><script><block s="doResetTimer"></block><block
s="doWaitUntil"><block s="reportOr"><block
s="reportGreaterThan"><block s="getTimer"></block><l>5</l></
block><block s="reportGreaterThan"><block
s="reportStringSize"><block s="reportURL"><block var="url"/></
block></block><l>1</l></block></block></block><block
s="doIfElse"><block s="reportLessThan"><block s="getTimer"></
block><l>5</l></block><script><block s="doReport"><block
s="reportBoolean"><l><bool>>true</bool></l></block></block></
script><script><block s="doReport"><block
s="reportBoolean"><l><bool>>false</bool></l></block></block></
script></block></script></block-definition><block-definition
s="%&apos;a&apos; max %&apos;b&apos;" type="reporter"
category="operators"><header></header><code></code><translations></
translations><inputs><input type="%n"></input><input type="%n"></
input></inputs><script><block s="doIf"><block
s="reportGreaterThan"><block var="a"/><block var="b"/></
block><script><block s="doReport"><block var="a"/></block></
script></block><block s="doReport"><block var="b"/></block></
script></block-definition><block-definition s="%&apos;a&apos; min
%&apos;b&apos;" type="reporter" category="operators"><header></
header><code></code><translations></translations><inputs><input
type="%n"></input><input type="%n"></input></inputs><script><block
s="doIf"><block s="reportLessThan"><block var="a"/><block var="b"/
></block><script><block s="doReport"><block var="a"/></block></
script></block><block s="doReport"><block var="b"/></block></
script></block-definition><block-definition s="$robot close mouth
%&apos;open&apos;" type="command" category="motion"><header></
header><code></code><translations></translations><inputs><input
type="%n"></input></inputs><script><custom-block s="$robot set
position(s) %n of motor(s) %s in %n seconds | wait ? %boolUE"><block
s="reportSum"><block s="reportProduct"><l>-55</l><block var="open"/
></block><l>25</l></block><l>m6</l><l>0</l><l><bool>>false</bool></
l></custom-block></script></block-definition><block-definition
s="$crosshairs hand pinch" type="reporter"
category="sensing"><header></header><code></code><translations></
translations><inputs></inputs><script><block s="doReport"><block
s="reportQuotient"><custom-block s="Leap pinch strength of hand
%n"><l>1</l></custom-block><l>100</l></block></block></script></
block-definition><block-definition s="$robot turn towards
%&apos;angle&apos;" type="command" category="motion"><header></
header><code></code><translations></translations><inputs><input
type="%n"></input></inputs><script><custom-block s="$robot set
position(s) %n of motor(s) %s in %n seconds | wait ? %boolUE"><block
s="reportProduct"><block var="angle"/><l>-75</l></block><l>m4</

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l><block s="reportQuotient"><block s="reportDifference"><l>10</l><block var="speed"/></block><l>10</l></block><l><bool>>false</bool></l></custom-block></script></block-definition><block-definition s="mirror 'num'; 'switch';" type="reporter" category="operators"><header></header><code></code><translations></translations><inputs><input type=""></input><input type=""></input></inputs><script><block s="doIf"><block var="switch"/><script><block s="doReport"><block s="reportProduct"><block var="num"/><l>-1</l></block></block></script></block><block s="doReport"><block var="num"/></block></script></block-definition><block-definition s="$robot face up / down 'angle';" type="command" category="motion"><header></header><code></code><translations></translations><inputs><input type=""></input></inputs><script><custom-block s="$robot set position(s) %n of motor(s) %s in %n seconds | wait ? %boolUE"><block s="reportProduct"><block var="angle"/><l>-50</l></block><l>m5</l><block s="reportQuotient"><block s="reportDifference"><l>10</l><block var="speed"/></block><l>10</l></block><l><bool>>false</bool></l></custom-block></script></block-definition><block-definition s="$crosshairs hand 'direction';" type="reporter" category="sensing"><header></header><code></code><translations></translations><inputs><input type=""><input type=""></inputs><script><block s="doReport"><custom-block s="Leap %txt rotation of hand %n"><block var="direction"/><l>1</l></custom-block></block></script></block-definition><block-definition s="$robot stand / sit 'height';" type="command" category="motion"><header></header><code></code><translations></translations><inputs><input type=""></input></inputs><script><custom-block s="$robot set position(s) %n of motor(s) %s in %n seconds | wait ? %boolUE"><block s="reportProduct"><block s="reportQuotient"><block s="reportDifference"><l>300</l><block s="reportDifference"><custom-block s="%n min %n"><custom-block s="%n max %n"><block var="height"/><l>200</l></custom-block><l>500</l></custom-block><l>200</l></block></block><l>300</l></block><l>90</l></block><l>m3</l><block s="reportProduct"><block s="reportQuotient"><block s="reportDifference"><l>10</l><block var="speed"/></block><l>10</l></block><l>2</l></block><l><bool>>false</bool></l></custom-block><custom-block s="$robot set position(s) %n of motor(s) %s in %n seconds | wait ? %boolUE"><block s="reportProduct"><block s="reportQuotient"><block s="reportDifference"><l>300</l><block s="reportDifference"><custom-block s="%n min %n"><custom-block s="%n max %n"><block var="height"/><l>200</l></custom-block><l>500</l></custom-block><l>200</l></block></block><l>300</l></block><l>-90</l></block><l>m2</l><block s="reportProduct"><block s="reportQuotient"><block s="reportDifference"><l>10</l><block var="speed"/></block><l>10</l></block><l>2</l></block><l><bool>>false</bool></l></custom-block></script></block-definition><block-definition s="$crosshairs hand 'y'; position" type="reporter" category="sensing"><header></header><code></code><translations></translations><inputs><input type=""><input type=""></inputs><script><block s="doReport"><custom-block s="Leap
```

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%txt position of hand %n"><block var="y"/><l>1</l></custom-block></
block></script></block-definition><block-definition s="Leap number
of hands" type="reporter" category="other"><header></header><code></
code><translations></translations><inputs></inputs><script><block
s="doReport"><block s="evaluate"><block
s="reportJSFunction"><list></list><l>return
window.controller.frame(0).hands.length;</l></block><list></list></
block></block></script></block-definition><block-definition s="Leap
%&apos;pos&apos;; position of hand %&apos;num&apos;" type="reporter"
category="other"><header></header><code></code><translations></
translations><inputs><input type="%txt"
readonly="true">x<options>x&#xD;y&#xD;z</options></input><input
type="%n">1</input></inputs><script><block
s="doDeclareVariables"><list><l>a</l></list></block><block
s="doIfElse"><block s="reportNot"><block
s="reportGreaterThan"><block var="num"/><custom-block s="Leap number
of hands"></custom-block></block></block><script><block
s="doReport"><block s="evaluate"><block
s="reportJSFunction"><list><l>pos</l><l>num</l></list><l>var a =
{x:0, y:1, z:2}[pos]; return
window.controller.frame(0).hands[num-1].stabilizedPalmPosition[a];</
l></block><list><block var="pos"/><block var="num"/></list></
block></block></script><script><block s="doReport"><l>0</l></
block></script></block></script></block-definition><block-definition
s="Leap %&apos;pos&apos;; rotation of hand %&apos;num&apos;"
type="reporter" category="other"><header></header><code></
code><translations></translations><inputs><input type="%txt"
readonly="true">yaw<options>yaw&#xD;pitch&#xD;roll</options></
input><input type="%n">1</input></inputs><script><block
s="doIfElse"><block s="reportNot"><block
s="reportGreaterThan"><block var="num"/><custom-block s="Leap number
of hands"></custom-block></block></block><script><block
s="doReport"><block s="evaluate"><block
s="reportJSFunction"><list><l>pos</l><l>num</l></list><l>var f =
window.controller.frame(0);&#xD;switch (pos){&#xD; case "yaw":&#xD;
return f.hands[num-1].yaw();&#xD; case "pitch":&#xD; return
f.hands[num-1].pitch();&#xD; case "roll":&#xD; return
f.hands[num-1].roll();&#xD;};&#xD; &#xD; </l></
block><list><block var="pos"/><block var="num"/></list></block></
block></script><script><block s="doReport"><l>0</l></block></
script></block></script></block-definition><block-definition s="Leap
%&apos;pos&apos;; position of finger %&apos;num&apos;"
type="reporter" category="other"><header></header><code></
code><translations></translations><inputs><input type="%txt"
readonly="true">x<options>x&#xD;y&#xD;z</options></input><input
type="%n">1</input></inputs><script><block s="doIfElse"><block
s="reportNot"><block s="reportGreaterThan"><block var="num"/><block
s="evaluate"><block s="reportJSFunction"><list></list><l>return
window.controller.frame(0).fingers.length;</l></block><list></
list></block></block></block><script><block s="doReport"><block
s="evaluate"><block s="reportJSFunction"><list><l>pos</l><l>num</
l></list><l>var a = {x:0, y:1, z:2}[pos]; return
window.controller.frame(0).fingers[num-1].stabilizedTipPosition[a];</
l></block><list><block var="pos"/><block var="num"/></list></

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block></block></script><script><block s="doReport"><l>0</l></
block></script></block></script></block-definition><block-definition
s="Leap hand &apos;num&apos;; is pinching" type="predicate"
category="other"><header></header><code></code><translations></
translations><inputs><input type="%s">1</input></
inputs><script><block s="doIfElse"><block s="reportNot"><block
s="reportGreaterThan"><block var="num"/><custom-block s="Leap number
of hands"></custom-block></block></block><script><block
s="doReport"><block s="reportGreaterThan"><block s="evaluate"><block
s="reportJSFunction"><list><l>num</l></list><l>return
window.controller.frame(0).hands[num-1].pinchStrength;</l></
block><list><block var="num"/></list></block><l>0.75</l></block></
block></script><script><block s="doReport"><block
s="reportBoolean"><l><bool>>false</bool></l></block></block></
script></block></script></block-definition><block-definition s="Leap
pinch strength of hand &apos;num&apos;." type="reporter"
category="other"><header></header><code></code><translations></
translations><inputs><input type="%n">1</input></
inputs><script><block s="doIfElse"><block s="reportNot"><block
s="reportGreaterThan"><block var="num"/><custom-block s="Leap number
of hands"></custom-block></block></block><script><block
s="doReport"><block s="reportProduct"><block s="evaluate"><block
s="reportJSFunction"><list><l>num</l></list><l>return
window.controller.frame(0).hands[num-1].pinchStrength;</l></
block><list><block var="num"/></list></block><l>100</l></block></
block></script><script><block s="doReport"><l>0</l></block></
script></block></script></block-definition><block-definition s="Leap
$flag" type="command" category="other"><header></header><code></
code><translations></translations><inputs></inputs><script><block
s="doIf"><block s="evaluate"><block s="reportJSFunction"><list></
list><l>return window.controller !== undefined</l></block><list></
list></block><script><block s="doStopThis"><l><option>this block</
option></l></block></script></block><block
s="doDeclareVariables"><list><l>test</l></list></block><block
s="doSetVar"><l>test</l><block s="evaluate"><block
s="reportJSFunction"><list></list><l>var leapScript,&#xD;    done =
false;&#xD; leapScript =
document.createElement(&apos;script&apos;),&#xD; leapScript.onload =
function () {&#xD;    done = true;&#xD;    console.log(&apos;leap is
ready&apos;);&#xD;};&#xD; document.head.appendChild(leapScript);&#xD;
leapScript.src = &apos;http://js.leapmotion.com/
leap-0.6.4.min.js&apos;;&#xD; return function () {return done; }</
l></block><list></list></block></block><block s="doWaitUntil"><block
s="evaluate"><block var="test"/><list></list></block></block><block
s="doRun"><block s="reportJSFunction"><list></
list><l>window.controller = new Leap.Controller({enableGestures:
true, background: true}); window.controller.connect();</l></
block><list></list></block></script></block-definition></
blocks><variables><variable name="host"><l>169.254.54.148</l></
variable><variable name="port"><l>6969</l></variable><variable
name="move name"><l>my first move</l></variable><variable
name="position snapshot"><list struct="atomic"
id="1472">92.82,-87.24,87.24,-4.84,-81.96,88.12</list></
variable><variable name="stretched"><list struct="atomic"

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```
id="1473">89.3,6.6,-55.57,3.08,-47.07,-21.26</list></  
variable><variable name="speed"><l>6</l></variable></variables></  
project>
```