

























宝莲灯机器人颜色代码表

速度

					
蜗牛速度	特慢	慢速	快速	特快	火箭速度
					





方向&炫酷动作

					
左转	直行	右转	向左变线	直行变线	向右变线
					
					
中途返回	终点返回	龙卷风转	前进摇摆	原地打转	后退摇摆
					



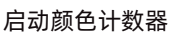

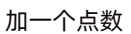







计时器

		
暂停3秒	开始计时(30秒后停止)	停止计时
		

获胜/退出

	
挑战成功(再玩一次)	挑战成功(游戏结束)
	

计数器

					
启动交叉点计数器	启动交叉点转向计数器	启动颜色计数器	启动点数计数器	加一个点数	减一个点数
					

宝莲灯机器人颜色代码表

速度

当宝莲灯机器人经过速度颜色代码时，会执行相应的速度。

- 蜗牛速度：3 秒的超慢速度指令。
- 特慢：一个缓慢的速度指令，直到机器人读取新的速度代码或关闭之前有效。
- 慢速：默认速度指令。
- 快速：一个快速指令，直到机器人读取新的速度代码或关闭之前有效。
- 特快：一种特快指令，在机器人读取新的速度代码或关闭之前有效。
- 火箭速度：3 秒的超快速度指令。

计时器

使用计时器颜色代码可以让机器人暂停、开始计时或停止计时。

- 开始计时 (30 秒后停止)：在经过“开始计时”指令后，宝莲灯机器人将在 30 秒后自动停止。在 30 秒内机器人可正常识别其他颜色代码，如识别到“停止计时”指令，宝莲灯将恢复默认行为。
- 停止计时：停止计时并继续默认行为。
- 暂停 3 秒：暂停 3 秒，然后继续默认行为。

方向

方向代码告诉你的宝莲灯机器人在交叉路口做什么。

- 左转：在下一个十字路口执行左转的指令。
- 直行：在下一个十字路口继续直行的指令。
- 右转：在下一个十字路口执行右转的指令。
- 向左变线：立即向左转 90 度，向前移动直到遇到新的线条，然后随机选择方向并沿着线条移动。
- 直行变线：在宝莲灯机器人遇到终点后，将继续向前行走直到发现新的线条。
- 向右变线：立即向右转 90 度，向前移动直到遇到新的线条，然后随机选择方向并沿着线条移动。
- 中途返回：当宝莲灯机器人遇到“中途返回”指令时，将旋转 180 度，沿着同一条线向相反方向行驶。
- 终点返回：当宝莲灯机器人遇到“终点返回”指令时，将旋转 180 度，沿着同一条线向相反方向行驶。

炫酷动作

- 龙卷风转：以增加的速度旋转两圈，然后沿着同一方向继续前进。
- 前进摇摆：向前移动时左右摇摆，然后继续直线移动的命令。
- 原地打转：命令以一致的速度旋转两圈，然后沿着同一方向继续旋转。
- 后退摇摆：快速转 180 度，向后摆动一秒钟，然后再转 180 度，并沿着同一方向继续走。

计数器

计数器颜色代码在计算 5 个交叉点、转弯或颜色代码时，机器人停止运行。

- 启动交叉点计数器：在经过“启动交叉点计数器”指令后，当你的宝莲灯机器人在经过第 5 个交叉点 (“T” 或 “+” 交叉点) 后自动停止，并闪烁红色。
- 启动交叉点转向计数器：在经过“启动交叉点转向计数器”指令后，一个类似于启动交叉点计数器的命令。不过机器人只计算它转弯的交叉点，不会计算直行的交叉点。
- 启动颜色计数器：在经过“启动颜色计数器”指令后，当你的宝莲灯机器人读取 5 种颜色后会自动停止。如宝莲灯机器人从红色到绿色线条的过渡，它就算作一种颜色的变化；不计算与黑色线条之间的过渡，也不计算长度小于 2 厘米的颜色线段。
- 启动点计数器：在经过“启动点计数器”指令后，每当宝莲灯读取“减 1 个数”时，它就会减 1 个数，当读取“加 1 个数”时，它就会加 1 个数。当加和减的总数等于“-5”时，宝莲灯机器人将自动停止并闪烁红色。

获胜/退出

这两个颜色代码让你的宝莲灯机器人庆祝成功，然后要么重新开始，要么停下来。

- 挑战成功 (再玩一次)：执行“成功”动画的指令，然后继续执行。
- 挑战成功 (游戏结束)：执行“成功”动画的指令，然后停止执行。

OZOBOT COLOR CODES

Speed



Short Super Slow



Slow



Cruise



Fast



Turbo



Nitro Boost



Direction & Special Moves



Left at Intersection



Straight at Intersection



Right at Intersection



Line Switch Left



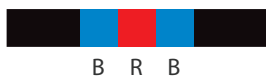
Line Switch Straight



Line Switch Right



U-Turn



U-Turn (line end)



Tornado



Zigzag



Spin



Backwalk



Timers



Pause (3 sec.)



Timer on (30 sec. to stop)



Timer off



Wins/Exits



Win/Exit (Play Again)



Win/Exit (Game Over)



Counters See reverse for definitions

Enable X-ing Counter



Enable Turn Counter



Enable Path Color Counter



Enable Point Counter



Point +1



Point -1



OZOBOT COLOR CODES

Speed

Speed codes change your Ozobot's velocity from Short Super Slow (slowest) to Nitro Boost (fastest).

- Short Super Slow
A three-second dose of super slow speed.
- Slow
A slow speed command effective until the bot reads a new speed code or is turned off.
- Cruise
The default speed command.
- Fast
A high speed command effective until the bot reads a new speed code or is turned off.
- Turbo
An extra high speed command effective until the bot reads a new speed code or is turned off.
- Nitro Boost
A three-second dose of Ozobot's highest speed.

Short Super Slow (slowest) > Slow > Cruise (default)
> Fast > Turbo > Nitro boost (fastest)

Cool Moves

Cool Move codes tell your Ozobot to bust a move!

- Tornado
A command to spin around twice at increasing speed, then continue following the line in the same direction.
- Zigzag
A command to sway right-left-right-left while moving forward, then continue moving straight.
- Spin
A command to spin around twice at a consistent speed, then continue following the line in the same direction.
- Backwalk
A command to quickly turn 180 degrees, wiggle backwards for one second, then turn 180 degrees again and continue following the line in the same direction.

Timer

Timer codes tell your Ozobot to pause or count seconds.

- Timer On (30 sec. to stop)
A command to make your Ozobot countdown from 30 sec., but continue to move and read codes while counting down. Ozobot will flash its light(s) at a rate of one flash/sec., flash rapidly to signify time is up, then shut off.
- Timer Off
A command to stop counting down seconds and return to default behavior.
- Pause (3 sec.)
A command to stop moving for three seconds, then continue with default behavior.

Direction

- Left at Intersection
A command to turn left at the next intersection.
- Straight at Intersection
A command to continue straight at the next intersection.
- Right at Intersection
A command to turn right at the next intersection.
- Line Switch Left
A command to immediately turn 90 degrees to the left, move forward to a new line, then make a random turn to follow along the new line.
- Line Switch Straight
A mid-line command to continue straight after the line ends. The code will not work if Ozobot encounters an intersection before the line ends.
- Line Switch Right
A command to immediately turn 90 degrees to the right, move forward to a new line, then make a random turn to follow along the new line.
- U-Turn
A mid-line command to turn around 180 degrees and follow the same line in the opposite direction.
- U-Turn (Line End)
A line-end command to turn around 180 degrees and follow the line in the opposite direction.

Counters

Counter codes tell your Ozobot to count five intersections, turns, or line color changes.

- Enable X-ing Counter
A command to make your Ozobot stop following lines after it crosses five intersections ('T' or '+' intersections). After the fifth intersection, Ozobot executes a "done" maneuver, stops following the line, and blinks red.
- Enable Turn Counter
A similar command to the Enable X-ing Counter, except that Ozobot only counts intersections where it makes a turn. It will not count intersections where it continues straight. Ozobot can randomly choose to go straight at an intersection, or be commanded to go straight with a "Straight at Intersection" code.
- Enable Path Color Counter
A command to make your Ozobot stop following lines after it reads five color changes in the line. If the line Ozobot is following transitions from red to green, it counts as one color change. Transitions to and from black lines are not counted, and color segments less than two centimeters in length are not counted.
- Enable Point Counter
A command that tells your Ozobot to count point codes down from five. Each time Ozobot reads a "Point -1" code it counts down. After the fifth "Point -1" code Ozobot will make a "done" maneuver, stop following lines, and blink red. You can add more to the total count (not to exceed five) with "Point +1" codes. You can reset Ozobot by turning it off, then on.

Wins/Exits

Win/Exit codes tell your Ozobot to celebrate its success, then either start over or stop.

- Win/Exit (Play Again)
A command to perform a "success" animation, then continue to follow the line.
- Win/Exit (Game Over)
A command to perform a "success" animation, then stop following the line.