#pragma config(Sensor, in1, armpot, sensorPotentiometer)

#pragma config(Sensor, dgtl1, clawswitch, sensorTouch)

#pragma config(Sensor, dgtl2, armswitch, sensorTouch)

#pragma config(Motor, port1, ltl, tmotorVex393HighSpeed\_HBridge, openLoop, reversed)

#pragma config(Motor, port2, ltm, tmotorVex393HighSpeed\_MC29, openLoop, reversed)

#pragma config(Motor, port3, ltt, tmotorVex393HighSpeed\_MC29, openLoop, reversed)

#pragma config(Motor, port4, clawl, tmotorVex393HighSpeed\_MC29, openLoop)

#pragma config(Motor, port5, ld, tmotorVex393HighSpeed\_MC29, openLoop)

#pragma config(Motor, port6, rd, tmotorVex393HighSpeed\_MC29, openLoop)

#pragma config(Motor, port7, clawr, tmotorVex393HighSpeed\_MC29, openLoop)

#pragma config(Motor, port8, rtm, tmotorVex393HighSpeed\_MC29, openLoop)

#pragma config(Motor, port9, rtt, tmotorVex393HighSpeed\_MC29, openLoop)

#pragma config(Motor, port10, rtl, tmotorVex393HighSpeed\_HBridge, openLoop)

//\*!!Code automatically generated by 'ROBOTC' configuration wizard !!\*//

void moveClaw( int time, int speed )

{

clearTimer(T1);

while( T1 <= time )

{

motor[ltl]=speed;

motor[ltm]=speed;

motor[ltt]=speed;

motor[rtl]=speed;

motor[rtm]=speed;

motor[rtt]=speed;

}

}

void moveRob( int time, int speed )

{

clearTimer(T1);

while( T1 <= time )

{

motor[rd]=speed;

motor[ld]=speed;

}

}

void motorsOff()

{

motor[ltl]=0;

motor[ltm]=0;

motor[ltt]=0;

motor[rtl]=0;

motor[rtm]=0;

motor[rtt]=0;

motor[rd]=0;

motor[ld]=0;

}

task main()

{

moveClaw( 1, 127 );

motorsOff();

moveRob( 3, 100 );

motorsOff();

}