enc_tgt()

Make the GoPiGo move till the encoder target is reached (distance targetting)

The encoder target can be enabled for one or for both of the motors. The target value is in steps and there are 18 steps in each wheel rotation. You can select the motors by using the select variable.

The GoPiGo stops once the target is reached and also makes the byte[0] of the status bit as 0.

You have to explicitly give a move command after setting the encoder target.

Syntax

```
enc_tgt(m1,m2,target)
```

Parameter:

m1: 0 to disable targeting for motor 1, 1 to enable it
m2: 0 to disable targeting for motor 2, 1 to enable it
target: number of encoder pulses to target (18 per rotation). For moving the wheel by 2 rotations, target should be 36

Return:

1 on success

-1 on error

Example

```
from gopigo import *
enc_tgt(1,1,72)
fwd()
```