# Cheatsheet Mecotron

**Reading user input:** float somevar = readValue(channel);

**Writing to Qrobotics:** writeValue(channel, encA\_value);

**Setting motor voltage:** setVoltageMotorA();  
 setVoltageMotofB();

**Inspecting sensors:**

*Position* float encA\_value = getPositionMotorA();

*Speed* getSpeedMotorA();

*Front Distance* getFrontDistance();

*Side Distance*  getSidedistance();

**Before uploading arduino:** ctrl+X

**Recording:**  ctrl+R