File: C:\Users\M4rc05\Documents\Vex\Starstruck\2223-G\3-29-2017\PID test.c

```
#pragma config(Sensor, dgtl1,  RightEncoder,    sensorQuadEncoder)
#pragma config(Sensor, dgtl3,  LeftEncoder,     sensorQuadEncoder)
#pragma config(Motor,  port1,           LeftMotor,     tmotorVex393 HBridge, openLoop, encoderPort, dgtl3)
#pragma config(Motor,  port10,          RightMotor,    tmotorVex393_HBridge, openLoop, reversed, encoderPort, dgtl1)
//*!!Code automatically generated by 'ROBOTC' configuration wizard               !!*//

task main(){
  while(SensorValue[RightEncoder]<=360 && SensorValue[LeftEncoder]<=360){ //loop to run until encoders are equal or greater than 360
                                                                          //(run until one revolution completed)
    motor[LeftMotor] = 50;  //move the left motor forward at a power of 50
    motor[RightMotor] = 50; //move the right motor forward at a power of 50
  }
  for(int c = 0; c<50; c++){  //loop to run for 50 milliseconds as a brake
    wait1Msec(1);
    motor[LeftMotor] = -50; //move the left motor backwards at a power of 50
    motor[RightMotor] = -50;  //move the right motor backwards at a power of 50
  }
}
```