#pragma config(Sensor, S1, touchSensor, sensorEV3\_Touch)

#pragma config(Sensor, S2, gyroSensor, sensorEV3\_Gyro, modeEV3Gyro\_RateAndAngle)

#pragma config(Sensor, S3, colorSensor, sensorEV3\_Color, modeEV3Color\_Color)

#pragma config(Sensor, S4, sonarSensor, sensorEV3\_Ultrasonic)

#pragma config(Motor, motorA, armMotor, tmotorEV3\_Large, PIDControl, encoder)

#pragma config(Motor, motorB, leftMotor, tmotorEV3\_Large, PIDControl, driveLeft, encoder)

#pragma config(Motor, motorC, rightMotor, tmotorEV3\_Large, PIDControl, driveRight, encoder)

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

task main()

{

moveMotorTarget(armMotor, 800, 100);

waitUntilMotorStop(armMotor);

}