

```
1  from threading import Thread
2
3
4  class toyRun(Thread):
5      def __init__(self, config):
6          self.config = config
7          self.drive = config.drive
8          self.arm = config.RMmotor
9          self.wait = config.timer.wait
10
11     def run(self):
12         self.drive.setHead()
13
14         self.drive.moveDist(320, heading=0)
15
16         self.drive.turnTo(40)
17         self.drive.moveDist(420, heading=40)
18         self.drive.turnTo(0)
19
20         self.drive.moveDist(280, heading=0)
21
22         self.drive.moveDist(-220, heading=0)
23         self.drive.spinTo(90)
24
25         self.drive.lineFollower(distance=50, mode=1,
26                                 speed=120, kp=0.3, ki=0, kd=0)
27
28         self.arm.run_angle(-600, 200)
29
30         self.drive.lineFollower(mode=1, speed=120, kp=0.3, ki=0, kd=0)
31         self.drive.setHead(90)
32
33         self.drive.moveLight(self.config.Rlight, [0, 10], heading=90)
34         self.drive.moveDist(270, heading=90)
35         self.drive.turnTo(120)
36
37         self.drive.moveDist(80, heading=120)
38
39         self.drive.moveDist(-60)
40         self.drive.turnTo(90)
41
42         self.drive.moveDist(500)
43         self.drive.spinTo(150)
44
45         self.drive.moveDist(-200)
46
47         self.config.state.setState(1)
48
```