**From Teleop**

**robot** = **robot**.*createRobotForTeleop*(**hardwareMap**, **telemetry**);

From Robot

**driveTrain** = DriveTrain.*DriveTrainTeleOp*(hardwareMap, telemetry);

From DriveTrain

**leftDriveMotor** = **new** DcMotor8863(RobotConfigMappingForGenericTest.*getleftMotorName*(), hardwareMap);  
**rightDriveMotor** = **new** DcMotor8863(RobotConfigMappingForGenericTest.*getrightMotorName*(), hardwareMap);

From DcMotor8863

**this**.setMode(DcMotor.RunMode.***STOP\_AND\_RESET\_ENCODER***);  
**this**.setPower(0);

from DriveTrain

**rightDriveMotor**.setMode(DcMotor.RunMode.***RUN\_WITHOUT\_ENCODER***);  
**leftDriveMotor**.setMode(DcMotor.RunMode.***RUN\_WITHOUT\_ENCODER***);  
**rightDriveMotor**.setPower(0);  
**leftDriveMotor**.setPower(0);