

Motors	Header Code	Example ==>	
Func	run(speed)		runs motor at a constant speed (degrees/sec) medium motor speed up to 1000, large up to 800 Example ==> <code>motor_A.run(200)</code>
Func	run_time(speed, time, then=Stop.HOLD, wait=True)		motor runs at a constant speed for given time in ms then stops and holds position waits to finish (or not) before next instruction Example ==> <code>motor_A.run_time(200, 500)</code>
Func	run_angle(speed, rotation_angle, then=Stop.HOLD, wait=True)		motor runs at a constant speed for a given angle then stops and holds position waits to finish (or not) before next instruction Example ==> <code>motor_A.run_angle(200, -180)</code>
Func	run_target(speed, target_angle, then=Stop.HOLD, wait=True)		motor runs at given speed to target_angle target_angle then stops and holds position waits to finish (or not) before next instruction Example ==> <code>motor_A.run_target(300, 180)</code>
Func	Stopping stop() brake() hold()	Stops the motor and lets it spin freely Passively brakes the motor - gradually stops Actively stops the motor - NOW	Example ==> <code>motor_A.stop()</code> <code>motor_A.brake()</code> <code>motor_A.hold()</code>

Robots	Header Code	Example ==>	
Func	straight(distance)		drives straight a given distance (mm) then stops Example ==> <code>robot.straight(200)</code>
Func	turn(angle)		turns in place by a given angle (degrees) Example ==> <code>robot.turn(-90)</code>
Func	drive(drive_speed, turn_rate)		drives at speed (MM/sec) & turn rate (deg/sec) Example ==> <code>robot.drive(-300, 45)</code>
Func	stop()		stops by letting motors spin freely Example ==> <code>robot.stop()</code>

Color Sensor	Header Code	Example ==>	
Func	color()		measures color of a surface Example ==> <code>print("color", sensor_1.color())</code>
Func	reflection()		measures reflection from surface using red light Example ==> <code>print("reflect", sensor_1.reflection())</code>