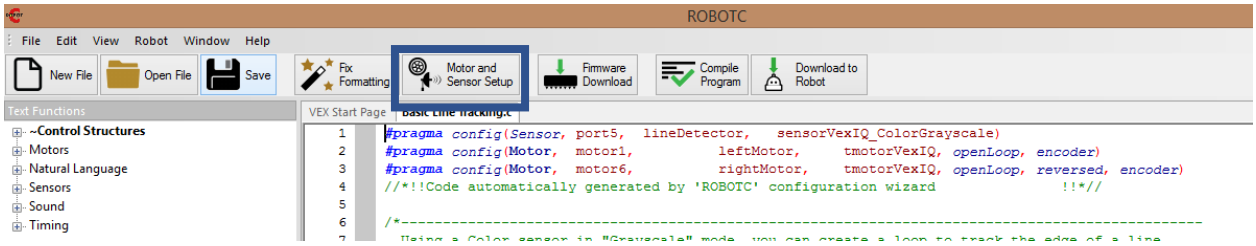
Start by opening up from the start menu **ROBOTC for VEX Robotics 4.X**

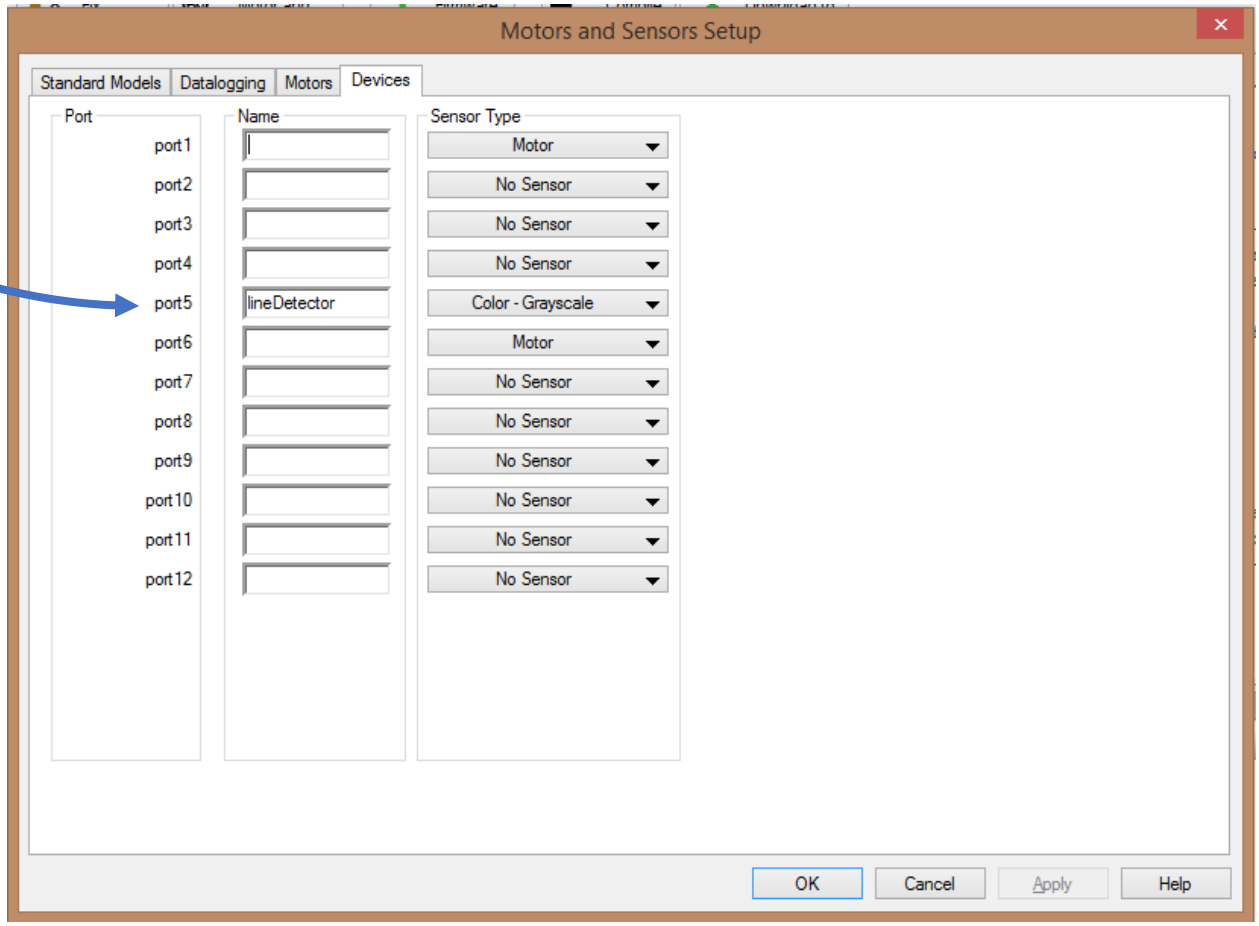
1- To start programming your robot, you need to designate which ports are being used by your VEX CPU.

On the main screen of the software, locate the **Motor and Sensor Setup** and click to open up the menu



The **Motors and Sensors Setup** dialog box will pop up. Type the name you will be designating your parts to in the **Name** category and under the **Sensor Type,** designate which sensor will be located on that specific port.

Refer to **port5** as an example: port5 = color sensor that measures Grayscale and is called "lineDetector"



This will generate your **Pragma** statements and will highlight them in Blue and Red.

2- It is common practice and good coding technique to put a brief description of what your code is going to do. Type a '***/**' to start a block of comments and a '/*' to end it.

```
/*---------------------------------------------------------------------------------------------
  Using a Color sensor in "Grayscale" mode, you can create a loop to track the edge of a line.
  This program will run forever (noted by the "while(true)" - the true condition will always be true)

  Note: Lighting conditions change from place to place, so the value '600' may need to be changed
  to better suit your environment. Grayscale Values can range from 0 to 2000 (possibly even higher)

                        ROBOT CONFIGURATION: VEX IQ Clawbot
  MOTORS & SENSORS:
  [I/O Port]          [Name]              [Type]                  [Location]
  Port 1              leftMotor           VEX IQ Motor            Left side motor
  Port 6              rightMotor          VEX IQ Motor            Right side motor (reversed)
  Port 5              lineDetector        VEX IQ Color            Color Detector (Grayscale Mode)
---------------------------------------------------------------------------------------------*/
task main()
{
```

3- Now begin your coding! The commands on the left side of your screen can be dragged and dropped within the coding area and modified for whatever task you are trying to accomplish.

Here is a little hint on how to get things moving

```
task main()
{
  //Forward
setMotor(LeftMotor, -127);
setMotor(RightMotor, 127);
wait(1.5,seconds);
stopAllMotors();
wait(.2,seconds);
```

Good Luck!