```python
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# Use this example for digital pin control of an H-bridge driver
# like a DRV8833, TB6612 or L298N.

# For wiring, see https://lastminuteengineers.com/stepper-motor-l298n-
arduino-tutorial/

import time
import board
import digitalio
from adafruit_motor import stepper

# Set DELAY as the length of time that the motor runs for each step.
# Adafruit suggests 0.01, but ME 30 folks have found this delay value
# needs to be much shorter. If 0.01 doesn't work, try something as short
# as 0.005.

DELAY = 0.01

# Set the number of steps for one rotation of the motor. For the
# stepper motor in the ME 30 kit, one rotation takes 200 steps.

STEPS = 200

# You can use any available GPIO pin on both a microcontroller and a
Raspberry Pi.
# The following pins are simply a suggestion. If you use different
pins, update
# the following code to use your chosen pins.

# To use with CircuitPython and a microcontroller:
coils = (
    digitalio.DigitalInOut(board.D9),   # A1
    digitalio.DigitalInOut(board.D10),  # A2
    digitalio.DigitalInOut(board.D11),  # B1
    digitalio.DigitalInOut(board.D12),  # B2
)

# To use with a Raspberry Pi:
# coils = (
#     digitalio.DigitalInOut(board.D19),  # A1
#     digitalio.DigitalInOut(board.D26),  # A2
#     digitalio.DigitalInOut(board.D20),  # B1
#     digitalio.DigitalInOut(board.D21),  # B2
# )

for coil in coils:
    coil.direction = digitalio.Direction.OUTPUT
```

```python
motor = stepper.StepperMotor(coils[0], coils[1], coils[2], coils[3],
microsteps=None)

# Each for loop below represents just one approach to taking a step.
# Your final code should choose one of them.
# For more info on what these different commands mean, see
# the "Stepper Motors" section of this page:
# https://learn.adafruit.com/adafruit-stepper-dc-motor-featherwing/
circuitpython

for step in range(STEPS):
    motor.onestep()
    time.sleep(DELAY)

for step in range(STEPS):
    motor.onestep(direction=stepper.BACKWARD)
    time.sleep(DELAY)

for step in range(STEPS):
    motor.onestep(style=stepper.DOUBLE)
    time.sleep(DELAY)

for step in range(STEPS):
    motor.onestep(direction=stepper.BACKWARD, style=stepper.DOUBLE)
    time.sleep(DELAY)

for step in range(STEPS):
    motor.onestep(style=stepper.INTERLEAVE)
    time.sleep(DELAY)

for step in range(STEPS):
    motor.onestep(direction=stepper.BACKWARD,
style=stepper.INTERLEAVE)
    time.sleep(DELAY)

motor.release()
```