```
void runAuton() {                          //delay(n) pauses robot to
 prevent inertial interference from previous move
    armAutonSeek = 0;                      //Seek 0. This should
     essentially do nothing since it's the beginning of auton

    driveForward(-377,8000);               //Roll back. Passes ball to
     BallBot intake
    delay(1200);
    driveForward(870,8000);                //Forward to corner
    delay(1000);

    //200deg turn = 90 deg irl
    turnMotorsAt(-300*colorMultiplier);    //Make 135 degree turn so
     claw faces platforms
    delay(1000);
    driveForward(-100,5000);               //Back in a bit further
    turnMotorsAt(120*colorMultiplier);     //Turn 45 deg, so claw faces
     opponent's side.
    delay(1000);
    driveForward(-350,8000);               //Slams backwards into wall
     to self-align
    delay(1000);
    driveForward(1000,9900);               //Engage w/ cap
    driveMotorsAt(0);

    delay(1000);

    armAutonSeek = POLE_HEIGHT_DEGS + 100; //Raise arm to just above
     pole
    delay(1200);
    turnMotorsAt(120*colorMultiplier);     //Turn towards the pole
    flipCap();                    //Turn the cap over 180 deg
    delay(500);
    armAutonSeek = POLE_HEIGHT_DEGS -200   //Lower cap onto pole
    delay(500);

    driveForward(-304,8000);           //Back out of cap
    delay(500);
    armAutonSeek = 0;                      //Put arm back down
    delay(500);

    turnMotorsAt(-120);               //Turn ccw so that claw faces
     other cap
    delay(500);
    driveForward(450,12000);           //Forward into cap
    delay(500);

    turnMotorsAt(170);               //Turn cw to knock ball out from
     under cap
    delay(500);

    driveForward(-1100,12000);           //Drive back into wall,
     slamming into it to re-align
    delay(1000);
    driveForward(350,12000);           //Drive out towards opposing
     side

    delay(1000);
    turnMotorsAt(230);               //Turn cw so claw faces back wall

    delay(500);

    driveForward(-800,12000);           //Drive backwards to that
     robot is to the left of the platform
    delay(1000);

    armAutonSeek = 377;               //Arm up so that it doesn't jam
     under the platform
    turnMotorsAt(-200);               //Slam into wall to align
    delay(1000);

    driveForward(400,3000);           //Slowly drive up to platform,
     gently touching it to align again
    driveMotorsAt(0);               //Stop completely

    delay(1000);

    driveForward(1200,12000);           //Run motor for a long time to
     get onto platform
    driveMotorsAt(0);
}
```