



2 left turns JAVA

```
package org.firstinspires.ftc.teamcode;

import com.qualcomm.robotcore.eventloop.opmode.LinearOpMode;
import com.qualcomm.robotcore.eventloop.opmode.TeleOp;
import com.qualcomm.robotcore.hardware.DcMotor;
import com.qualcomm.robotcore.hardware.DcMotorSimple;

@TeleOp(name="Lesson4", group="Tutorial")
public class Lesson1 extends LinearOpMode {
    // create DcMotor objects
    private DcMotor frontRight;
    private DcMotor frontLeft;
    private DcMotor backRight;
    private DcMotor backLeft;

    @Override
    public void runOpMode() {
        // initialize hardware variables
        frontRight = hardwareMap.get(DcMotor.class, "frontRight");
        frontLeft = hardwareMap.get(DcMotor.class, "frontLeft");
        backRight = hardwareMap.get(DcMotor.class, "backRight");
        backLeft = hardwareMap.get(DcMotor.class, "backLeft");

        // Set motor direction
        frontRight.setDirection(DcMotorSimple.Direction.REVERSE);
        backRight.setDirection(DcMotorSimple.Direction.REVERSE);

        waitForStart();

        // when started
        if (opModeIsActive()) {

            // drive forward
            frontRight.setPower(1);
            frontLeft.setPower(1);
            backRight.setPower(1);
            backLeft.setPower(1);
            telemetry.addData("Driving", "Forward");
            telemetry.update();
            sleep(1100);
        }
    }
}
```



```
// stop
frontRight.setPower(0);
frontLeft.setPower(0);
backRight.setPower(0);
backLeft.setPower(0);
sleep(100);

// turn left
frontRight.setPower(0.5);
frontLeft.setPower(-0.5);
backRight.setPower(0.5);
backLeft.setPower(-0.5);
sleep(250);

// drive forward
frontRight.setPower(1);
frontLeft.setPower(1);
backRight.setPower(1);
backLeft.setPower(1);
sleep(1500);

// stop
frontRight.setPower(0);
frontLeft.setPower(0);
backRight.setPower(0);
backLeft.setPower(0);
sleep(100);

// turn left
frontRight.setPower(0.5);
frontLeft.setPower(-0.5);
backRight.setPower(0.5);
backLeft.setPower(-0.5);
sleep(250);

// drive forward
frontRight.setPower(1);
frontLeft.setPower(1);
backRight.setPower(1);
backLeft.setPower(1);
sleep(2000);

// stop
frontRight.setPower(0);
```



```
frontLeft.setPower(0);  
backRight.setPower(0);  
backLeft.setPower(0);  
sleep(100);
```

```
}  
}  
}
```