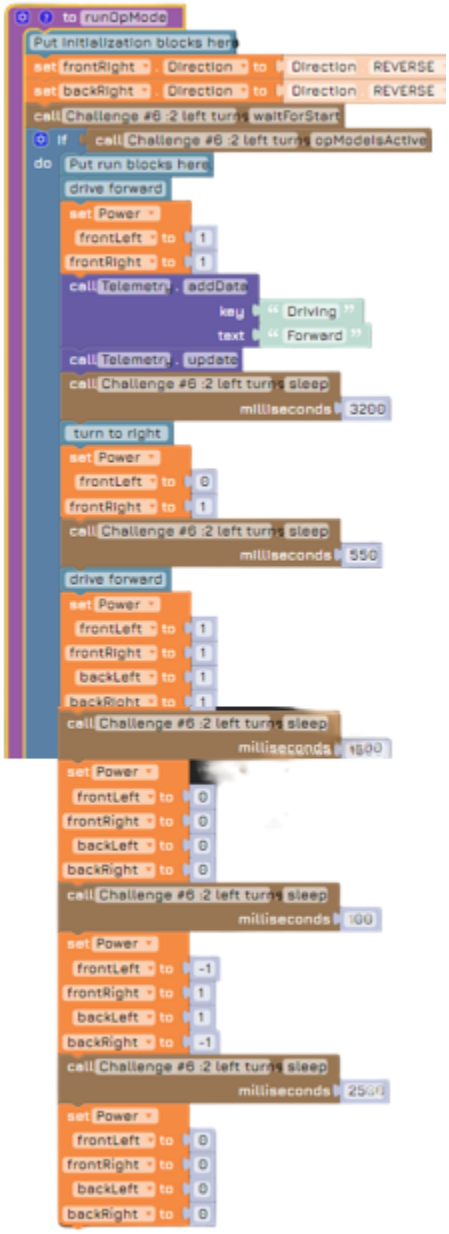
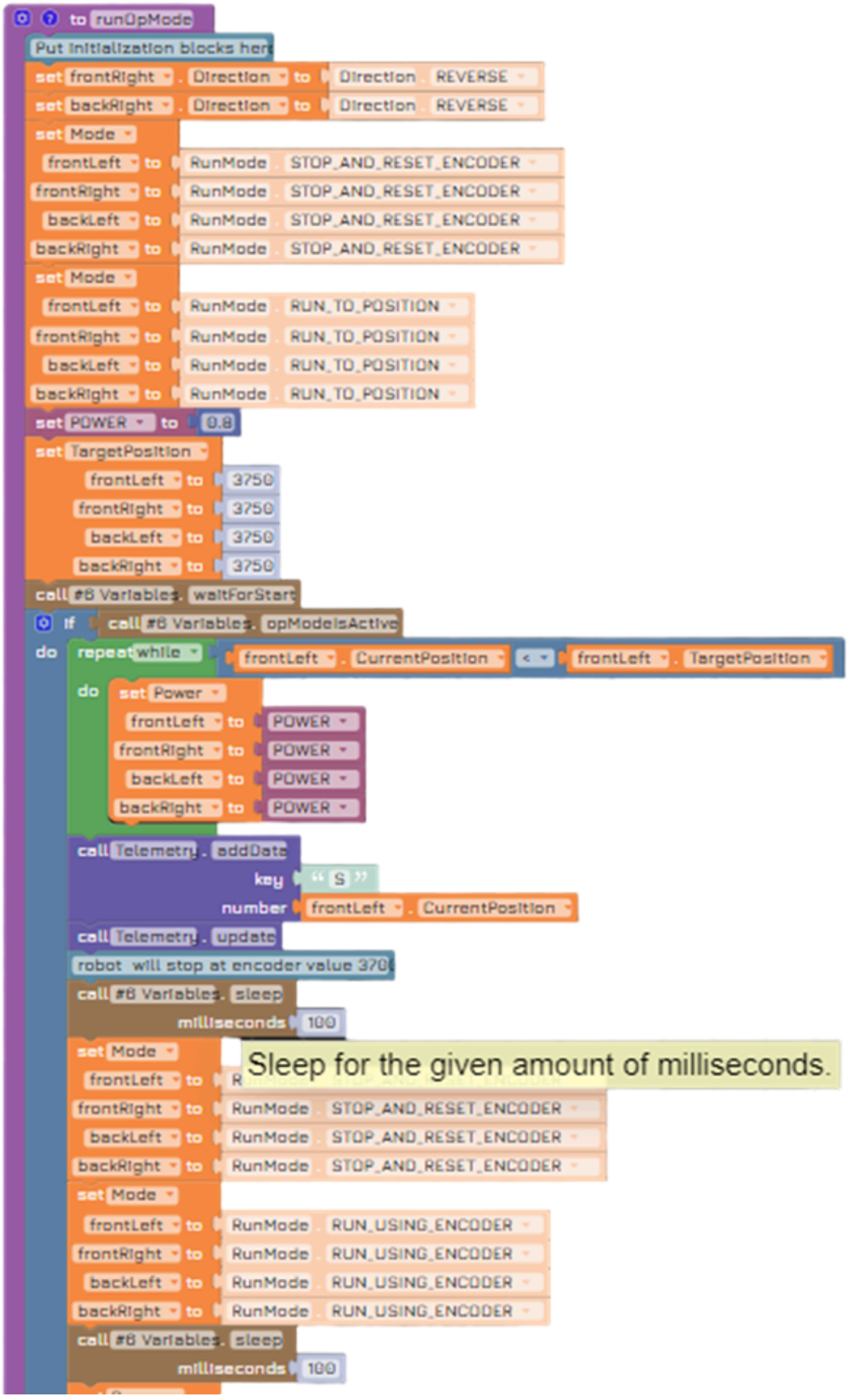
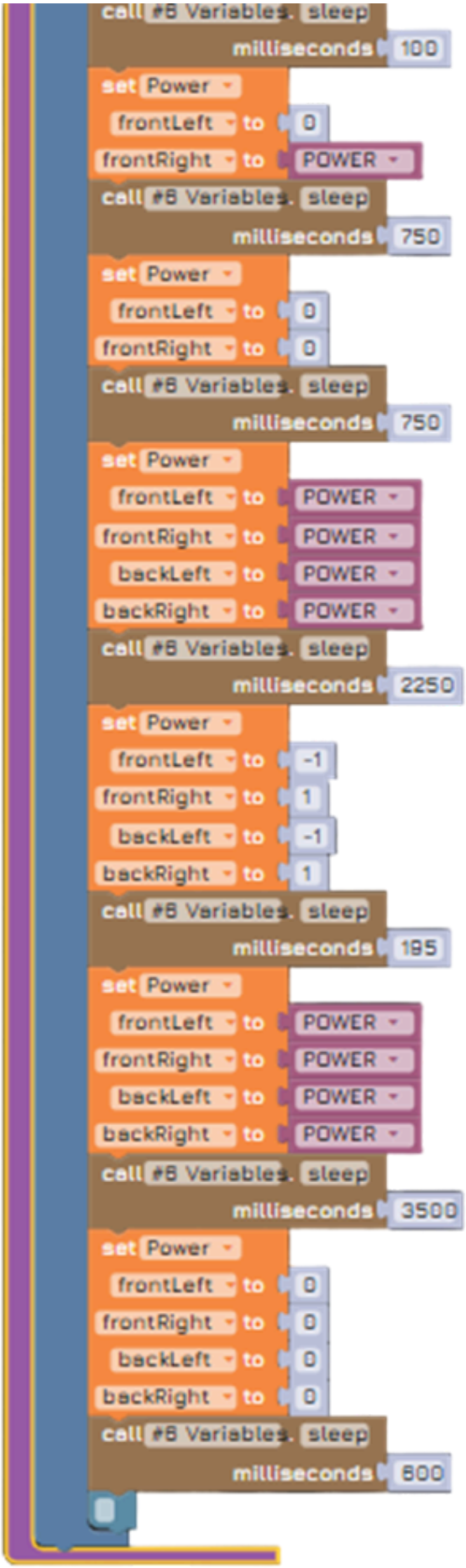
Challenge #6 Multiple Solutions
2 left turns using time Scroll down for JAVA



Using Variables/Encoders




call #8 Variables. sleep
milliseconds 100
set Power
frontLeft to 0
frontRight to POWER
call #8 Variables. sleep
milliseconds 750
set Power
frontLeft to 0
frontRight to 0
call #8 Variables. sleep
milliseconds 750
set Power
frontLeft to POWER
frontRight to POWER
backLeft to POWER
backRight to POWER
call #8 Variables. sleep
milliseconds 2250
set Power
frontLeft to -1
frontRight to 1
backLeft to -1
backRight to 1
call #8 Variables. sleep
milliseconds 185
set Power
frontLeft to POWER
frontRight to POWER
backLeft to POWER
backRight to POWER
call #8 Variables. sleep
milliseconds 3500
set Power
frontLeft to 0
frontRight to 0
backLeft to 0
backRight to 0
call #8 Variables. sleep
milliseconds 600


```
1.  package org.firstinspires.ftc.teamcode;
2.
3.  import com.qualcomm.robotcore.eventloop.opmode.LinearOpMode;
4.  import com.qualcomm.robotcore.eventloop.opmode.TeleOp;
5.  import com.qualcomm.robotcore.hardware.DcMotor;
6.  import com.qualcomm.robotcore.hardware.DcMotorSimple;
7.
8.  @TeleOp(name="Lesson4", group="Tutorial")
9.  public class Lesson1 extends LinearOpMode {
10.    // create DcMotor objects
11.    private DcMotor frontRight;
12.    private DcMotor frontLeft;
13.    private DcMotor backRight;
14.    private DcMotor backLeft;
15.
16.    @Override
17.    public void runOpMode() {
18.          // initialize hardware variables
19.       frontRight = hardwareMap.get(DcMotor.class, "frontRight");
20.       frontLeft = hardwareMap.get(DcMotor.class, "frontLeft");
21.       backRight = hardwareMap.get(DcMotor.class, "backRight");
22.       backLeft = hardwareMap.get(DcMotor.class, "backLeft");
23.
24.       // Set motor direction
25.       frontRight.setDirection(DcMotorSimple.Direction.REVERSE);
26.       backRight.setDirection(DcMotorSimple.Direction.REVERSE);
27.
28.
29.       waitForStart();
30.
31.       // when started
32.       if (opModeIsActive()) {
33.
34.          // drive forward
35.           frontRight.setPower(1);
36.           frontLeft.setPower(1);
37.           backRight.setPower(1);
38.           backLeft.setPower(1);
39.          telemetry.addData("Driving", "Forward");
40.          telemetry.update();
41.           sleep(1100);
42.
43.          // stop
44.          frontRight.setPower(0);
45.           frontLeft.setPower(0);
46.           backRight.setPower(0);
```

```
47.          backLeft.setPower(0);
48.         sleep(100);
49.
50.         // turn left
51.         frontRight.setPower(0.5);
52.          frontLeft.setPower(-0.5);
53.          backRight.setPower(0.5);
54.          backLeft.setPower(-0.5);
55.         sleep(250);
56.
57.          // drive forward
58.          frontRight.setPower(1);
59.          frontLeft.setPower(1);
60.          backRight.setPower(1);
61.          backLeft.setPower(1);
62.          sleep(1500);
63.
64.         // stop
65.         frontRight.setPower(0);
66.          frontLeft.setPower(0);
67.          backRight.setPower(0);
68.          backLeft.setPower(0);
69.         sleep(100);
70.
71.         // turn left
72.         frontRight.setPower(0.5);
73.          frontLeft.setPower(-0.5);
74.          backRight.setPower(0.5);
75.          backLeft.setPower(-0.5);
76.         sleep(250);
77.
78.        // drive forward
79.          frontRight.setPower(1);
80.          frontLeft.setPower(1);
81.          backRight.setPower(1);
82.          backLeft.setPower(1);
83.          sleep(2000);
84.
85.         // stop
86.         frontRight.setPower(0);
87.          frontLeft.setPower(0);
88.          backRight.setPower(0);
89.          backLeft.setPower(0);
90.         sleep(100);
91.
92.
```


```
93.
94.         }
95.     }
96.}
```