```
runOpMode
 Put initialization blocks here.
  set frontRight . Direction . to
                                    Direction
                                               REVERSE
  set backRight -
                  . Direction • to
                                    Direction
                                               REVERSE
  call lift wobble goal . waitForStart
  opModelsActive
  do lift wobble
       call Telemetry . update
      set Power
       frontLeft - to ( 0.2
      frontRight - to 0.2
       call lift wobble goal . sleep
                     milliseconds | 200
      set wobbleActuator - . Power
       call lift wobble goal . sleep
                     milliseconds 500
      set Power -
       frontLeft - to
                      0 1
      frontRight - to [
      ready to drive with wobble goal
       call lift wobble goal . sleep
                     milliseconds 📋 3400
      set Power
       frontLeft - to 0 0
      frontRight - to 0 0
       call lift wobble goal . sleep
                     milliseconds | 500
      set Power -
       frontLeft -
                        1
      frontRight *
       backLeft - to
                        1
      backRight - to
       call lift wobble goal . sleep
                     milliseconds | 600
```

Alternative Code Wobble Position #1

```
to runOpMode
  Put initialization blocks here.
  set Speed ▼ to 0.75
  set frontRight . Direction to Direction .
                                           REVERSE
  set backRight . Direction to
                                 Direction
                                           REVERSE
  if call Lesson6 . opModelsActive
  do Put run blocks here.
      set wobbleActuator . Power to [1]
      set Power •
      frontLeft v to Speed v
      frontRight v to Speed v
      backLeft v to Speed v
      backRight v to Speed v
      call Lesson6 . sleep
             milliseconds
                           950 ÷ 🔻
                                      Speed •
      set Power *
      frontLeft v to l - v Speed v
      frontRight v to Speed v
      backLeft v to Speed v
      backRight v to C-v Speed v
      call Lesson6 . sleep
             milliseconds 350
      set wobbleActuator . Power to 0
      set Power •
      frontLeft v to [ 0
      frontRight v to 00
      backLeft to 00
      backRight v to [ 0
      call Lesson6 . sleep
             milliseconds 1000
      set Power v
      frontLeft v to Speed v
                           Speed 🔻
      frontRight v to
       backLeft v to
                           Speed *
```

```
call Lesson6 . sleep
       milliseconds 1000
set Power •
frontLeft v to Speed v
frontRight v to U - v U Speed v
backLeft v to l - v Speed v
backRight v to Speed v
call Lesson6 . sleep
       milliseconds 575
set Power v
frontLeft v to Speed v
frontRight v to Speed v
backLeft to Speed v
backRight v to Speed v
call Lesson6 . sleep
       milliseconds 350 ÷ 1
                                 Speed 1
set Power *
frontLeft v to 00
frontRight v to 00
backLeft to 00
backRight v to 00
call Lesson6 . sleep
       milliseconds 1000
```