

### Mac - Terminal Commands

<code>ls</code>	Displays contents of the current directory(folder)
<code>cd [PATH FILE]</code>	Navigates into the directory specified by the path file given
<code>cd ..</code>	Navigates "up" a folder from current directory
<code>mkdir [FOLDER NAME]</code>	Creates a new directory inside the current directory
<code>touch [FILENAME.EXTENSTION]</code>	Creates a new file in the current directory with name and filetype specified

### Windows - Command Prompt Commands

<code>dir</code>	Displays contents of the current directory(folder)
<code>cd [PATH FILE]</code>	Navigates into the directory specified by the path file given
<code>cd ..</code>	Navigates "up" a folder from current directory
<code>mkdir [FOLDER NAME]</code>	Creates a new directory inside the current directory
<code>type nul &gt; [FILENAME.EXTENSTION]</code>	Creates a new file in the current directory with name/filetype specified

### Common Python Syntax

<code>if (condition):</code>	#Reminder syntax for conditional statement
<code>#must tab for code to execute when true</code>	
<code>elif(condition):</code>	
<code>#must tab for code to execute when true</code>	
<code>else:</code>	
<code>#must tab for code to execute in other cases</code>	
<code>number = 5</code>	#Creating an integer variable
<code>name = "Suzy"</code>	#Creating a string variable
<code>while(condition):</code>	#Example code for while loop
<code>#must tab for all code to execute</code>	
<code>#continually while condition is true</code>	
<code>for [NUMBER] in range(x,y):</code>	#Example code of a for loop
<code>#must tab for all code to execute</code>	

### Helpful PyParrot/Python Commands

<code>connect(num_retries = INTEGER)</code>	#Connects to drone, on failure will retry specified # of times
<code>disconnect()</code>	#Disconnects from drone
<code>safe_takeoff(timeout = INTEGER)</code>	#Initiates takeoff, on failure will retry until specified # of seconds
<code>safe_land(timeout = INTEGER)</code>	#Initiates landing, on failure will retry until specified # of seconds
<code>set_max_tilt(degrees = INTEGER)</code>	#ALWAYS SET AT 10, sets the max tilt (-100 to 100)
<code>set_max_vertical_speed(speed = INTEGER)</code>	#ALWAYS SET AT 10, sets the max vertical speed in m/s
<code>flat_trim()</code>	#Sets default flat setting based on the drones position at time of call
<code>smart_sleep(seconds = INTEGER)</code>	#"Sleeps" the specified number of seconds
 <code>fly_direct(roll = INTEGER, pitch = INTEGER, yaw = INTEGER, vertical_movement = INTEGER, duration = INTEGER)</code>	 #Directs the drone how to fly according to Roll, Pitch, Yaw, a vertical movement and how long to fly in this state.
 <code>turn_degrees(degrees = INTEGER)</code>	 #Turns the drone the specified degrees in the clockwise direction for positive value and counter-clockwise for negative value.
 <code>print("text")</code>	 #Prints what's inside of the parenthesis
<code>input(String)</code>	