

```
#include <kipr/wombat.h>
int main()
{
  printf("Going straight");

  motor (0,-80); // turn
  motor (3,-80);
  msleep (1000);

  return 0;
}
```

Type after the
printf ("Turning"); function

Notes:

msleep (1000);

motor (3,-80);

The time your robot will
travel in milliseconds.
From 0-10,000

The port # your motor is
plugged into

Place a negative (-) before the
power number. Positive numbers go
forward and negative numbers go
backwards.
Power can only be from -100 to
100

The closer the wheels powers are to each other, the straighter it will go.



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