

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

    // turning right
    motor(0,80); // left wheel
    motor(3,40); // right wheel
    msleep(1000);

    return 0;
}
```

Type after the
printf("Turning"); function

Notes:
msleep(1000);
motor(3,40);

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

The port # your motor is
plugged into

Lower the power of one of the wheels.
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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