

Lab 8C Run 2

```
//First quarter
reverse(4);
motorSpeed(4,20);
goToRelativePosition(470);
reverse(4);
motorSpeed(4,60);
goFor(.5);
brake(4);
goFor(7); //stop at gate for 7 seconds

//2nd quarter
reverse(4);
motorSpeed(4,20);
goToRelativePosition(475);
celerate(4,20,0,2);
goFor(1);

//3rd quarter
//start back with r2 unit
reverse(4); //don't do this if servo design
motorSpeed(4,35);
goToRelativePosition(475);
reverse(4);
motorSpeed(4,60);
goFor(.5);
brake(4);
goFor(7); //brake at gate for 7 seconds

//4th quarter
reverse(4);
motorSpeed(4,20);
goToRelativePosition(475);
reverse(4);
motorSpeed(4,60);
goFor(.5);
brake(4);
```