**Robot Type**
Choose which robot you want to write a program for. Note that not including this command defaults to "robotType(none);" Also please note that this command should be the first thing in your "task main()."

Command:

```
robotType(type);
```

Parameters: `type`

**Valid Robot Types for type:**
- **none** - this will not set up any motors and sensors for you (this is the default.)
- **rembot** - sets the motors and sensors to match a default REMBOT.

Usage without Parameters:

```
robotType();
```

This snippet of code will set the robot type to **none** by default, skipping the setup process. You must manually set the motors and sensors in the 'Motors and Sensors Setup' menu.

Usage with Parameters:

```
robotType(rembot);
```

This snippet of code will set the robot type to **rembot**. This will automatically set up the motor and sensor ports to match those of a default REMBOT.
**Start Motor**
Set a motor to a speed.

Command:

```
startMotor(motor, speed);
```

Parameters: motor, speed

Acceptable Motors for motor:
MOTOR ports A through C (and your names for them given in Motors and Sensors Setup.)

Valid Range Values for speed:
(reverse) -100 to 100 (forward) where 0 is stop.

Usage without Parameters:
```
startMotor();
wait();
stopMotor();
```

This snippet of code will run the motor in motor-port A at speed 75 for 1.0 seconds and then stop it. The default motor-port is `motorA` and the default speed is 75 for `startMotor()`.

Usage with Parameters:
```
startMotor(motorB, -25);
wait(0.5);
stopMotor(motorB);
```

This snippet of code will run the motor in motor-port B at speed -25 for 0.5 seconds and then stop it.

---

**Stop Motor**
Stops a motor.

Command:

```
stopMotor(motor);
```

Parameters: motor

Acceptable Motors for motor:
MOTOR ports A through C (and your names for them given in Motors and Sensors Setup.)

Usage without Parameters:
```
startMotor();
wait();
stopMotor();
```

This snippet of code will run the motor in motor-port A at speed 75 for 1.0 seconds and then stop it. The default motor-port is `motorA` for `stopMotor()`.

Usage with Parameters:
```
startMotor(motorB, -25);
wait(0.5);
stopMotor(motorB);
```

This snippet of code will run the motor in motor-port B at speed -25 for 0.5 seconds and then stop it.
Wait Functions:

**Wait**

Wait an amount of time measured in seconds. The robot continues to do what it was doing during this time.

Command:

```plaintext
wait(time);
```

**Parameters:** time

**Valid Range Values for time:**

0.0 to 3600.0 and up.

Usage without Parameters:

```plaintext
forward();
wait();
stop();
```

This snippet of code will run the robot forward for 1.0 seconds and then stop. The default time is 1.0 (seconds) for `wait()`.

Usage with Parameters:

```plaintext
forward(50);
wait(2.73);
stop();
```

This snippet of code will run the robot forward at half speed for 2.73 seconds and then stop.

---

**Wait in Milliseconds**

Wait an amount of time measured in milliseconds. The robot continues to do what it was doing during this time.

Command:

```plaintext
waitInMilliseconds(time);
```

**Parameters:** time

**Valid Range Values for time:**

0 to 3600000 and up.

Usage without Parameters:

```plaintext
forward();
waitInMilliseconds();
stop();
```

This snippet of code will run the robot forward for 1000 milliseconds (1.0 seconds) and then stop. The default time is 1000 (milliseconds) for `waitInMilliseconds()`.

Usage with Parameters:

```plaintext
forward(50);
waitInMilliseconds(2730);
stop();
```

This snippet of code will run the robot forward at half speed for 2730 milliseconds (2.73 seconds) and then stop.
Robot Movement Functions:

Note that for desirable results with the following set of functions, you must use the "robotType();" Setup Function with type rembot in the beginning of your "task main()".

Forward

Both wheels rotate forward at the same speed, causing the robot to move forward.

Command:

```c
forward(speed);
```

Parameters: speed

Valid Range Values for speed:
0 to 100 (however forward() will always move your robot forward.)

Usage without Parameters:

```c
forward();
wait();
stop();
```

This snippet of code will run the robot forward for 1.0 seconds and then stop. The default speed is 75 for forward().

Usage with Parameters:

```c
forward(50);
wait(2.0);
stop();
```

This snippet of code will run the robot forward at half speed for 2.0 seconds and then stop.

Backward

Both wheels rotate backward at the same speed, causing the robot to move backward.

Command:

```c
backward(speed);
```

Parameters: speed

Valid Range Values for speed:
-100 to 0 (however backward() will always move your robot backward.)

Usage without Parameters:

```c
backward();
wait();
stop();
```

This snippet of code will run the robot backward for 1.0 seconds and then stop. The default speed is -75 for backward().

Usage with Parameters:

```c
backward(-50);
wait(2.0);
stop();
```

This snippet of code will run the robot backward at half speed for 2.0 seconds and then stop.
Point Turn
Both wheels rotate at the same speed but in opposite directions, causing the robot to turn in place.

Command:

\[
\text{pointTurn}(\text{direction}, \text{speed});
\]

Parameters: direction, speed

Valid Directions for direction: left and right.

Valid Range Values for speed: -100 to 100.

Usage without Parameters:

\[
\begin{align*}
\text{pointTurn}() \\
\text{wait}() \\
\text{stop}()
\end{align*}
\]

This snippet of code will make the robot turn right in place at speed 75 for 1.0 seconds and then stop. The default direction and speed are right and 75 for pointTurn().

Usage with Parameters:

\[
\begin{align*}
\text{pointTurn}(\text{left}, 50) \\
\text{wait}(0.4) \\
\text{stop}()
\end{align*}
\]

This snippet of code will make the robot turn left in place at half speed for 0.4 seconds.

Swing Turn
One wheel rotates while the other does not move, causing the robot to make a wide turn around the stopped wheel.

Command:

\[
\text{swingTurn}(\text{direction}, \text{speed});
\]

Parameters: direction, speed

Valid Directions for direction: left and right.

Valid Range Values for speed: -100 to 100.

Usage without Parameters:

\[
\begin{align*}
\text{swingTurn}() \\
\text{wait}() \\
\text{stop}()
\end{align*}
\]

This snippet of code will make the robot make a wide right turn at speed 75 for 1.0 seconds and then stop. The default direction and speed are right and 75 for swingTurn().

Usage with Parameters:

\[
\begin{align*}
\text{swingTurn}(\text{left}, 50) \\
\text{wait}(0.75) \\
\text{stop}()
\end{align*}
\]

This snippet of code will make the robot make a wide left turn at half speed for 0.75 seconds.
**Stop**
Both wheels do not move, causing the robot to stop.

Command:
```
stop();
```

**Parameters:** N/A

Usage without Parameters:
```
forward();
wait();
stop();
```
This snippet of code will run the robot forward for 1.0 seconds and then stop. (Note that there are no parameters for `stop()`.

Usage with Parameters:
```
forward(50);
wait(2.0);
stop();
```
This snippet of code will run the robot forward at half speed for 2.0 seconds and then stop.

---

**Line Track for Time**
The robot will track a dark line on a light surface for a specified time in seconds.

Command:
```
lineTrackForTime(time, threshold, sensorPort);
```

**Parameters:** `time`, `threshold`, `sensorPort`

**Valid Range Values for `time`:**
0 to 3600.0 and up.

**Valid Range Values for `threshold`:**
(dark) 0 to 100 (light).

**Acceptable Sensors for `sensorPort`:**
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

Usage without Parameters:
```
lineTrackForTime();
stop();
```
This snippet of code will make the robot follow a dark line on a light surface for 5.0 seconds using a threshold of 45 and a light sensor in sensor-port S3 and then stop. These values and sensors are the defaults for `lineTrackForTime()`.

Usage with Parameters:
```
lineTrackForTime(7.5, 75, S2);
stop();
```
This snippet of code will make the robot follow a dark line on a light surface for 7.5 seconds, using a threshold of 75 and a light sensor in sensor-ports 2 and then stop.
**Line Track for Rotations**
The robot will track a dark line on a light surface for a specified distance in encoder rotations.

```plaintext
Command:

lineTrackForRotations(rotations, threshold, sensorPort);
```

**Parameters:** rotations, threshold, sensorPort

**Valid Range Values for rotations:**
0 to 65000.0 and up.

**Valid Range Values for threshold:**
(dark) 0 to 100 (light).

**Acceptable Sensors for sensorPort:**
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

**Usage without Parameters:**
```
lineTrackForRotations();
stop();
```

**Usage with Parameters:**
```
lineTrackForRotations(4.75, 75, S2);
stop();
```

This snippet of code will make the robot follow a dark line on a white surface for 4.75 rotations, using a threshold of 75 and a light sensor in sensor-port S2 and then stop.

This snippet of code will make the robot follow a dark line on a white surface for 3.0 rotations using a threshold of 45 and a light sensor in sensor-ports S3 and then stop. These values and sensors are the defaults for lineTrackForRotations().
**Move Straight for Time**
The robot will use encoders to maintain a straight course for a specified length of time in seconds.

Command:

```
moveStraightForTime(time, rightMotorEncoder, leftMotorEncoder);
```

**Parameters:** time, rightMotorEncoder, leftMotorEncoder

**Valid Range Values for time:**
0 to 3600.0 and up.

**Acceptable Sensors for rightMotorEncoder, leftMotorEncoder:**
MOTOR ports A through C (and your names for them given in Motors and Sensors Setup.)

**Usage without Parameters:**
```
moveStraightForTime();
stop();
```

This snippet of code will make the robot move forward, maintaining a straight heading for 5.0 seconds using the built-in encoders on motor-ports motorB and motorC, and then stop. These values and sensors are the defaults for `moveStraightForTime()`.

**Usage with Parameters:**
```
moveStraightForTime(7.5, motorC, motorA);
stop();
```

This snippet of code will make the robot move forward, maintaining a straight heading for 7.5 seconds using the built-in encoders on motor-ports C and A, and then stop.

**Move Straight for Rotations**
The robot will use encoders to maintain a straight course for a specified distance in rotations.

Command:

```
moveStraightForRotations(time, rightMotorEncoder, leftMotorEncoder);
```

**Parameters:** rotations, rightMotorEncoder, leftMotorEncoder

**Valid Range Values for rotations:**
0 to 65000.0 and up.

**Acceptable Sensors for rightEncoder, leftEncoder:**
MOTOR ports A through C (and your names for them given in Motors and Sensors Setup.)

**Usage without Parameters:**
```
moveStraightForRotations();
stop();
```

This snippet of code will make the robot move forward, maintaining a straight heading for 1.0 rotations using the built-in encoders on motor-ports motorB and motorC, and then stop. These values and sensors are the defaults for `moveStraightForRotations()`.

**Usage with Parameters:**
```
moveStraightForRotations(4.75, motorC, motorA);
stop();
```

This snippet of code will make the robot move forward, maintaining a straight heading for 4.75 rotations using the built-in encoders on motor-ports C and A, and then stop.
Tank Control
The robot will be remote controlled in such a way that the right motor is mapped to the right joystick and the left motor is mapped to the left joystick.

Command:
\[
\text{tankControl}(\text{rightJoystick}, \ \text{leftJoystick}, \ \text{threshold});
\]

Parameters: rightJoystick, leftJoystick, threshold
Valid Channels for rightJoystick, leftJoystick:
Any of the "joystick." channels will work, however joystick.joy1_y2 and joystick.joy1_y1 make the most sense for this application.

Usage without Parameters:
\[
\text{while(true)}
\{
\quad \text{tankControl();}
\}
\]

Usage with Parameters:
\[
\text{while(true)}
\{
\quad \text{tankControl(joystick.joy1_y1, joystick.joy1_y2, 5);}\]
\]

This snippet of code will remote control the robot using "tank control" with a "dead" threshold of 10. The default right and left joysticks and threshold are joystick.joy1_y2, joystick.joy1_y1, and 10 for tankControl().

Arcade Control
The robot will be remote controlled in such a way that the movement of the robot is mapped to a single joystick, much like a retro arcade game.

Command:
\[
\text{arcadeControl(verticalJoystick, horizontalJoystick, threshold);}\]

Parameters: verticalJoystick, horizontalJoystick, threshold
Valid Channels for verticalJoystick, horizontalJoystick:
Any of the "joystick." channels will work, however joystick.joy1_y2 and joystick.joy1_x2 make the most sense for this application.

Usage without Parameters:
\[
\text{while(true)}
\{
\quad \text{arcadeControl();}
\}
\]

Usage with Parameters:
\[
\text{while(true)}
\{
\quad \text{arcadeControl(joystick.joy1_y1, joystick.joy1_x2, 5);}\]
\]

This snippet of code will remote control the robot using "arcade control" with a "dead" threshold of 10. The default vertical and horizontal joysticks and threshold are joystick.joy1_y2, joystick.joy1_x2, and 10 for tankControl().
Until Functions:

**Until Touch**
The robot continues what it was doing until the touch sensor is pressed in.

**Command:**
```
untilTouch(sensorPort);
```

**Parameters:** `sensorPort`

**Acceptable Sensors for `sensorPort`:**
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

**Usage without Parameters:**
```
forward();
untilTouch();
stop();
```

This snippet of code will run the robot forward until the touch sensor in sensor-port 1 is pressed, and then stop. The default sensor port is `S1` for `untilTouch()`.

**Usage with Parameters:**
```
forward(50);
untilTouch(S3);
stop();
```

This snippet of code will run the robot forward at half speed until the touch sensor in sensor-port 3 is pressed, and then stop.

**Until Release**
The robot continues what it was doing until the touch sensor is released out.

**Command:**
```
untilRelease(sensorPort);
```

**Parameters:** `sensorPort`

**Acceptable Sensors for `sensorPort`:**
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

**Usage without Parameters:**
```
forward();
untilRelease();
stop();
```

This snippet of code will run the robot forward until the touch sensor in sensor-port 1 is released, and then stop. The default sensor port is `S1` for `untilRelease()`.

**Usage with Parameters:**
```
forward(50);
untilRelease(S3);
stop();
```

This snippet of code will run the robot forward at half speed until the touch sensor in sensor-port 3 is released, and then stop.
Until Bump
The robot continues what it was doing until the touch sensor is pressed in and then released out. (A delay time in milliseconds can be specified as well.)

Command:
```plaintext
untilBump(sensorPort, delayTimeMS);
```

Parameters: `sensorPort`, `delayTimeMS`

Acceptable Sensors for `sensorPort`:
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

Valid Range Values for `delayTimeMS`:
0 to 3600000 and up.

Usage without Parameters:
```plaintext
forward();
untilBump();
stop();
```

This snippet of code will run the robot forward until the touch sensor in sensor-port 1 is pressed in and then released out, and then stop. The default sensor port and delay time are `S1` and `10` for `untilBump()`.

Usage with Parameters:
```plaintext
forward(50);
untilBump(S3, 100);
stop();
```

This snippet of code will run the robot forward at half speed until the touch sensor in sensor-port 3 is pressed in and then released out (with a delay of 100ms), and then stop.

Until Button Press
The robot continues what it was doing until a specified button on the NXT is pressed.

Command:
```plaintext
untilButtonPress(lcdButton);
```

Parameters: `lcdButton`

Valid LCD Buttons for `lcdButton`:
centerBtnNXT - NXT orange center button
rightBtnNXT - NXT right button
leftBtnNXT - NXT left button

Usage without Parameters:
```plaintext
forward();
untilButtonPress();
stop();
```

This snippet of code will run the robot forward until a button on the NXT is pressed. The default button is `centerBtnNXT` for `untilBtnPress()`.

Usage with Parameters:
```plaintext
forward(50);
untilButtonPress(rightBtnNXT);
stop();
```

This snippet of code will run the robot forward at half speed until the right button on the NXT is pressed.
**Until Sonar Greater Than**
The robot continues what it was doing until the sonar sensor reads a value greater than a set distance in centimeters.

Command:

```
untilSonarGreaterThan(distance, sensorPort);
```

**Parameters:** `distance`, `sensorPort`

**Acceptable Values for distance:**
0 to 647 (cm).

**Acceptable Sensors for sensorPort:**
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

Usage without Parameters:

```
forward();
untilSonarGreatherThan();
stop();
```

This snippet of code will run the robot forward until the sonar sensor in sensor-port 4 reads a value greater than 30 centimeters, and then stop. The default distance and sensor ports are 30 and S4 for `untilSonarGreaterThan()`.

Usage with Parameters:

```
forward(50);
untilSonarGreaterThan(45, S2);
stop();
```

This snippet of code will run the robot forward at half speed until the sonar sensor in sensor-port 2 reads a value greater than 45 centimeters, and then stop.

---

**Until Sonar Less Than**
The robot continues what it was doing until the sonar sensor reads a value less than a set distance in centimeters.

Command:

```
untilSonarLessThan(distance, sensorPort);
```

**Parameters:** `distance`, `sensorPort`

**Acceptable Values for distance:**
0 to 647 (cm).

**Acceptable Sensors for sensorPort:**
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

Usage without Parameters:

```
forward();
untilSonarLessThan();
stop();
```

Usage with Parameters:

```
forward(50);
untilSonarLessThan(45, S2);
stop();
```

This snippet of code will run the robot forward until the sonar sensor in sensor-port 4 reads a value less than 30 centimeters, and then stop. The default distance and sensor ports are 30 and S4 for `untilSonarLessThan()`.

This snippet of code will run the robot forward at half speed until the sonar sensor in sensor-port 2 reads a value less than 45 centimeters, and then stop.
Until Dark
The robot continues what it was doing until the line tracking sensor reads a value darker than a specified threshold.

Command:
```
untilDark(threshold, sensorPort);
```

Parameters: threshold, sensorPort

Valid Range Values for threshold:
(dark) 0 to 100 (light)

Acceptable Sensors for sensorPort:
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

Usage without Parameters:
```
forward();
untilDark();
stop();
```

Usage with Parameters:
```
forward(50);
untilDark(75, S1);
stop();
```

This snippet of code will run the robot forward until the light sensor in sensor-port 3 reads a value darker than 45, and then stop. The default threshold and sensor port are 45 and S3 for `untilDark()`.

This snippet of code will run the robot forward at half speed until the light sensor in sensor-port 1 reads a value darker than 75, and then stop.

Until Light
The robot continues what it was doing until the line tracking sensor reads a value lighter than a specified threshold.

Command:
```
untilLight(threshold, sensorPort);
```

Parameters: threshold, sensorPort

Valid Range Values for threshold:
(dark) 0 to 100 (light)

Acceptable Sensors for sensorPort:
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

Usage without Parameters:
```
forward();
untilLight();
stop();
```

Usage with Parameters:
```
forward(50);
untilLight(15, S1);
stop();
```

This snippet of code will run the robot forward until the light sensor in sensor-port 3 reads a value lighter than 45, and then stop. The default threshold and sensor port are 45 and S3 for `untilDark()`.

This snippet of code will run the robot forward at half speed until the light sensor in sensor-port 1 reads a value lighter than 15, and then stop.
**Until Sound Greater Than**
The robot continues what it was doing until the sound sensor reads a value greater than a set threshold level.

**Command:**
```
untilSoundGreaterThan(threshold, sensorPort);
```

**Parameters:** threshold, sensorPort

**Acceptable Values for threshold:**
(quiet) 0 to 100 (loud).

**Acceptable Sensors for sensorPort:**
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

**Usage without Parameters:**
```
forward();
untilSoundGreaterThan();
stop();
```

This snippet of code will run the robot forward until the sound sensor in sensor-port 2 reads a value greater than 50, and then stop. The default threshold and sensor ports are 50 and S2 for untilSoundGreaterThan().

**Usage with Parameters:**
```
forward(50);
untilSoundGreaterThan(85, S3);
stop();
```

This snippet of code will run the robot forward at half speed until the sound sensor in sensor-port 3 reads a value greater than (louder than) 85, and then stop.

---

**Until Sound Less Than**
The robot continues what it was doing until the sound sensor reads a value less than a set threshold level.

**Command:**
```
untilSoundLessThan(threshold, sensorPort);
```

**Parameters:** distance, sensorPort

**Acceptable Values for threshold:**
(quiet) 0 to 100 (loud).

**Acceptable Sensors for sensorPort:**
SENSOR ports 1 through 4 (and your names for them given in Motors and Sensors Setup.)

**Usage without Parameters:**
```
forward();
untilSoundLessThan();
stop();
```

This snippet of code will run the robot forward until the sound sensor in sensor-port 2 reads a value quieter than 50, and then stop. The default threshold and sensor ports are 50 and S2 for untilSoundLessThan().

**Usage with Parameters:**
```
forward(50);
untilSoundLessThan(15, S3);
stop();
```

This snippet of code will run the robot forward at half speed until the sound sensor in sensor-port 3 reads a value less than (quieter than) 15, and then stop.
Until Rotations
The robot continues what it was doing until the motor encoder rotations reach the desired value.

Command:

```
untilRotations(rotations, motorEncoderPort);
```

Parameters: rotations, sensorPort

Valid Range Values for rotations:
0.0 to 65000.0 and up.

Acceptable Sensors for sensorPort:
MOTOR ports A through C (and your names for them given in Motors and Sensors Setup.)

Usage without Parameters:

```
forward();
untilRotations();
stop();
```

This snippet of code will run the robot forward for 1.0 rotations using a built-in encoder on motor-port B, and then stop. The default rotations and sensor port are 1.0 and motorB for untilRotations().

Usage with Parameters:

```
forward(50);
untilRotations(2.75, motorA);
stop();
```

This snippet of code will run the robot forward at half speed for 2.75 rotations using a built-in encoder on motor-port A, and then stop.

Until Encoder Counts
The robot continues what it was doing until the motor encoder counts reach the desired value.

Command:

```
untilEncoderCounts(counts, sensorPort);
```

Parameters: counts, sensorPort

Valid Range Values for counts:
0 to 65000 and up.

Acceptable Sensors for sensorPort:
MOTOR ports A through C (and your names for them given in Motors and Sensors Setup.)

Usage without Parameters:

```
forward();
untilEncoderCounts();
stop();
```

This snippet of code will run the robot forward for 360 encoder counts (1.0 rotations) using a built-in encoder on motor-port B, and then stop. The default rotations and sensor port are 360 and motorB for untilEncoderCounts().

Usage with Parameters:

```
forward(50);
untilEncoderCounts(990, motorA);
stop();
```

This snippet of code will run the robot forward at half speed for 990 encoder counts (2.75 rotations) using a built-in encoder on motor-port A, and then stop.