```java
package org.firstinspires.ftc.teamcode;

import com.qualcomm.robotcore.eventloop.opmode.LinearOpMode;
import com.qualcomm.robotcore.hardware.CRServo;
import com.qualcomm.robotcore.eventloop.opmode.Autonomous;
import com.qualcomm.robotcore.eventloop.opmode.TeleOp;
import com.qualcomm.robotcore.eventloop.opmode.Disabled;
import com.qualcomm.robotcore.hardware.DcMotor;
import com.qualcomm.robotcore.hardware.DcMotorSimple;
import com.qualcomm.robotcore.util.ElapsedTime;


@Autonomous(name="CR Center", group="CR")

public class CR_Center extends LinearOpMode {


    private ElapsedTime runtime = new ElapsedTime();

    private CRServo grippers;

    @Override
    public void runOpMode() {
        telemetry.addData("Status", "Initialized");
        telemetry.update();

        grippers=hardwareMap.crservo.get("glyphArm");

        waitForStart();
        runtime.reset();


        while (opModeIsActive()) {
            telemetry.addData("Status", "Run Time: " +
runtime.toString());

            grippers.setPower(.5);


            telemetry.update();


        }
    }
}
```