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package org.firstinspires.ftc.teamcode;

import com.qualcomm.robotcore.eventloop.opmode.TeleOp;
import com.qualcomm.robotcore.hardware.HardwareDevice;
import com.qualcomm.robotcore.hardware.DistanceSensor;
import com.qualcomm.robotcore.hardware.ColorSensor;
import com.qualcomm.robotcore.hardware.CRServo;
import com.qualcomm.robotcore.hardware.Servo;
import com.qualcomm.robotcore.hardware.DcMotor;
import com.qualcomm.robotcore.eventloop.opmode.OpMode;

@TeleOp (name="Tele-Op", group="Tele-Op")

public class Driving extends OpMode{

    DcMotor leftWheel;

    DcMotor rightWheel;

    DcMotor pulley;

    DcMotor relicArm;

    Servo colorArm;

    CRServo wrist;

    Servo finger;

    Servo leftGripper;

    Servo rightGripper;

    ControlClass controlClass;

    RelicClass relicClass;

    @Override
    public void init()
    {

        leftWheel = hardwareMap.dcMotor.get("leftWheel");

        rightWheel = hardwareMap.dcMotor.get("rightWheel");

        leftWheel.setDirection(DcMotor.Direction.REVERSE);

        pulley = hardwareMap.dcMotor.get("pulley");

        pulley.setZeroPowerBehavior(DcMotor.ZeroPowerBehavior.BRAKE);

        relicArm = hardwareMap.dcMotor.get("relicArm");

        relicArm.setZeroPowerBehavior(DcMotor.ZeroPowerBehavior.BRAKE);
    }
}

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    colorArm = hardwareMap.servo.get("colorArm");

    wrist = hardwareMap.crservo.get("wrist");

    finger = hardwareMap.servo.get("finger");

    leftGripper = hardwareMap.servo.get("leftGripper");

    rightGripper = hardwareMap.servo.get("rightGripper");

    controlClass = new ControlClass (leftWheel, rightWheel,
pulley, colorArm, leftGripper, rightGripper, false, false);

    relicClass = new RelicClass (relicArm, wrist, finger);

    controlClass.stopDriving();

    controlClass.stopPulley();

    controlClass.liftArm();

}

@Override
public void start()
{

}

@Override
public void loop()
{

    controlClass.controllerDrive (gamepad1);

    relicClass.controlRelicArm (gamepad2);

}

@Override
public void stop()
{

    controlClass.stopDriving();

    controlClass.stopPulley();

}

}

```