**Purpose:** The event manager is the common class used by all autonomous opmodes to control the other parts of the program. The event manager instantiates (creates an instance of) each EPS (Navigation and Actions), and starts each running in its own thread. This class uses list(s) of events from a configuration file or object specified by the opmode that creates it. Each configuration can contain a different combination and order of Navigation and Actions events, allowing for multiple different autonomous opmodes to be created fairly easily.

|  |  |
| --- | --- |
| **Priority:** High | **Reason:** This class sets up and assists the other important autonomous classes. |

**Primary Programmers:**

* <Team Member 1>
* <Team Member 2>

**Public Constants (public static final):**

* <required type if any> <NAME>
  + Purpose: <1-4 sentences> Lorem ipsum dolor sit amet, consectetur adipiscing elit. Pellentesque in turpis posuere, pretium velit in, tempor turpis.
* public static final int MAX\_MOTOR\_POWER
  + Purpose: The maximum value for motor power. Should be used in algorithms like motor scaling and course correction.

**Constructors (called when an object instance is created):**

* public <Class Name>(<#> arguments)
  + Must Initialize: <Minimum initialization it must preform>
  + Arguments:
    - <required type if applicable> <arg1>
      * <purpose>

**Interface Instance Methods (used on an instance of this class):**

* public <other tags> <return type> <method name>(<#> arguments)
  + Purpose: <1-4 sentences> Lorem ipsum dolor sit amet, consectetur adipiscing elit. Pellentesque in turpis posuere, pretium velit in, tempor turpis.
  + Priority: <Same options as the class priority> (<reason>)
  + Arguments:
    - <type> <arg1>
      * What to put there (see also: <something else in this file>)
  + Returns: (<type>) <what data is returned>
    - <Can go onto a separate bullet(s) if it would be cleaner>
* public synchronized void setPower(1 argument)
  + Purpose: Adjust the motor power, and start or stop it when necessary.
  + Priority: Very High (cannot start the motor without it)
  + Arguments:
    - int power
      * The power to set the motor to (see also: MAX\_MOTOR\_POWER)
  + Returns: N/A
* public synchronized void stopMotor(0 arguments)
  + Purpose: Stop the motor, syntactically equivalent to ‘setPower(0)’.
  + Priority: Medium (only a shortcut method, but all it needs to do is call setPower(0))
  + Arguments: N/A
  + Returns: N/A

**Interface Static Methods (used without an instance of a class):**

* public static synchronized long getCurrentTime(1 argument)
  + Purpose: Get how much time has elapsed, syntactically equivalent to ‘System.currentTimeMillis() - someothertime’
  + Priority: Low (prevents other programmers from having to do this manually every time)
  + Arguments:
    - long start
      * when this ‘timer’ started (specify 0 to get an initial start time)
  + Returns: (long) the current system time in milliseconds