Driver Control

* Tank Control (Deadband)
* Arcade Control

Autonomous

RAJA::Drive drive(l\_motor, r\_motor, imu);

* Absolute movement absolute\_move
* Relative movement relative\_move
* Move to point move\_to\_point(
* Motion Profile
* Path Following follow(drive, vector);

Absolute\_move(drive1, sensor\_used

Absolute\_move(drive1, sensor\_used, max\_speed, max\_settle\_time);

Drive1.left\_move( get\_calculated\_power(

PID Controller

Chassis Object:

Constructor (Chassis (right\_motors, left\_motors,

Move forward and backwards

* Enter in the sensor used
* Enter in the drive object
* Enter in the PID used

Move\_absolute(drive1, LinearPID,