package org.firstinspires.ftc.teamcode;

import com.qualcomm.robotcore.eventloop.opmode.LinearOpMode;

import com.qualcomm.robotcore.eventloop.opmode.TeleOp;

import com.qualcomm.robotcore.hardware.DcMotor;

import com.qualcomm.robotcore.hardware.DcMotorSimple;

import com.qualcomm.robotcore.hardware.Servo;

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

public class TELEOP\_Copy extends LinearOpMode {

private DcMotor frontleft;

private DcMotor backright;

private Servo Latch;

private Servo claw;

private DcMotor arm;

private DcMotor backleft;

private DcMotor frontright;

/\*\*

\* This function is executed when this Op Mode is selected from the Driver Station.

\*/

@Override

public void runOpMode() {

frontleft = hardwareMap.dcMotor.get("front left");

backright = hardwareMap.dcMotor.get("back right ");

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

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

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

backleft = hardwareMap.dcMotor.get("back left");

frontright = hardwareMap.dcMotor.get("front right ");

frontleft.setDirection(DcMotorSimple.Direction.REVERSE);

backright.setDirection(DcMotorSimple.Direction.REVERSE);

Latch.setDirection(Servo.Direction.REVERSE);

Latch.setPosition(0);

claw.setPosition(.6);

frontleft.setZeroPowerBehavior(DcMotor.ZeroPowerBehavior.FLOAT);

frontright.setZeroPowerBehavior(DcMotor.ZeroPowerBehavior.FLOAT);

backleft.setZeroPowerBehavior(DcMotor.ZeroPowerBehavior.FLOAT);

backright.setZeroPowerBehavior(DcMotor.ZeroPowerBehavior.FLOAT);

// Put initialization blocks here.

waitForStart();

if (opModeIsActive()) {

while (opModeIsActive()) {

frontleft.setPower(-gamepad1.left\_stick\_x);

backright.setPower(gamepad1.left\_stick\_x);

backleft.setPower(-gamepad1.left\_stick\_x);

frontright.setPower(gamepad1.left\_stick\_x);

frontleft.setPower(-gamepad1.right\_stick\_x);

backright.setPower(-gamepad1.right\_stick\_x);

frontright.setPower(gamepad1.right\_stick\_x);

backleft.setPower(gamepad1.right\_stick\_x);

frontleft.setPower(gamepad1.left\_stick\_y);

frontright.setPower(gamepad1.left\_stick\_y);

backright.setPower(-gamepad1.left\_stick\_y);

backleft.setPower(-gamepad1.left\_stick\_y);

telemetry.addData("Left Front Power", frontleft.getPower());

telemetry.addData("Left Back Power", backleft.getPower());

telemetry.addData("Right Front Power", frontright.getPower());

telemetry.addData("Right Back Power", backright.getPower());

if (gamepad2.y) {

claw.setPosition(.5);

} else if (gamepad2.x) {

claw.setPosition(.95);

}

if (gamepad1.b) {

Latch.setPosition(0);

} else if (gamepad1.a) {

Latch.setPosition(1);

}

arm.setPower(gamepad2.left\_stick\_y / 1.48);

if (gamepad2.dpad\_right) {

arm.setPower(gamepad2.right\_stick\_y / 1);

}

telemetry.addData("Claw Position ", claw.getPosition());

telemetry.addData("Motor Power", arm.getPower());

telemetry.addData("Latch Position", Latch.getPosition());

telemetry.update();

}

// Put run blocks here.

}

}

}