```
#pragma config(Hubs,  S1, HTMotor,  HTMotor,  HTMotor,  HTMotor)
#pragma config(Hubs,  S2, HTServo,  none,     none,     none)
#pragma config(Sensor, S1,       ,               sensorI2CMuxController)
#pragma config(Sensor, S2,       ,               sensorI2CMuxController)
#pragma config(Motor,  mtr_S1_C1_1,     left2,          tmotorTetrix, openLoop,
#pragma config(Motor,  mtr_S1_C1_2,     right2,         tmotorTetrix, openLoop)
#pragma config(Motor,  mtr_S1_C2_1,     left,           tmotorTetrix, openLoop)
#pragma config(Motor,  mtr_S1_C2_2,     intake,         tmotorTetrix, openLoop)
#pragma config(Motor,  mtr_S1_C3_1,     launcher,       tmotorTetrix, openLoop)
#pragma config(Motor,  mtr_S1_C3_2,     right,          tmotorTetrix, openLoop)
#pragma config(Motor,  mtr_S1_C4_1,     lifter,         tmotorTetrix, openLoop)
#pragma config(Motor,  mtr_S1_C4_2,     motorK,         tmotorTetrix, openLoop)
#pragma config(Servo,  srvo_S2_C1_1,    grabber,
tServoContinuousRotation)
#pragma config(Servo,  srvo_S2_C1_2,    servo2,
tServoNone)
#pragma config(Servo,  srvo_S2_C1_3,    servo3,
tServoNone)
#pragma config(Servo,  srvo_S2_C1_4,    servo4,
tServoNone)
#pragma config(Servo,  srvo_S2_C1_5,    servo5,
tServoNone)
#pragma config(Servo,  srvo_S2_C1_6,    servo6,
tServoNone)
//*!!Code automatically generated by 'ROBOTC' configuration wizard
!!*//

#include "JoystickDriver.c"

const int driveType = 1;

task main()
{
  while(true)
  {
    //each stick controls a motor
    getJoystickSettings(joystick);

    if (driveType == 0) {

      if(joystick.joy1_y1<20 && joystick.joy1_y1>-20){
        motor[left] = 0;
        motor[left2] = 0;
        }else{
        motor[left] = -joystick.joy1_y1;
        motor[left2] = joystick.joy1_y1;
      }
      if(joystick.joy1_y2<20 && joystick.joy1_y2>-20){
        motor[right] = 0;
        motor[right2] = 0;
```

```
      }else{
        motor[right] = joystick.joy1_y2;
        motor[right2] = joystick.joy1_y2;
      }
    } else if (driveType == 1) {
    int leftIn = joystick.joy1_y1;
    int leftPwr = leftIn * leftIn / 127;
    if (leftIn < 0) {
      leftPwr = leftPwr * -1;
    }
    motor[left] = -leftPwr;
    motor[left2] = leftPwr;
    int rightIn = joystick.joy1_y2;
    int rightPwr = rightIn * rightIn / 127;
    if (rightIn < 0) {
      rightPwr = rightPwr * -1;
    }
    motor[right] = rightPwr;
    motor[right2] = rightPwr;
  }
  if(joy1Btn(6)){
    motor[intake] = -100;
    motor[launcher] = 100;
    }else if(joy1Btn(8)){
    motor[intake] = 100;
    motor[launcher] = -100;
    }else{
    motor[intake] = 0;
    motor[launcher] = 0;
  }
  if(joy1Btn(2)){
    servo[grabber] = 0;
  }else if(joy1Btn(1)){
    servo[grabber] = 127;
  }

  //added jan 7
  if(joy1Btn(5)){
    motor[lifter] = 100;
  }else if(joy1Btn(7)){
    motor[lifter] = -100;
  }
  else{
    motor[lifter] = 0;
  }
  }
}
```