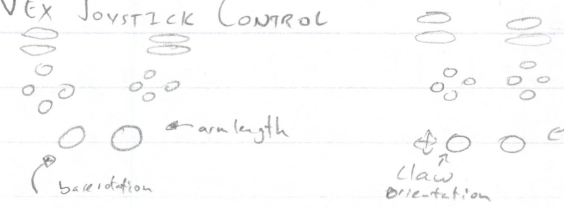
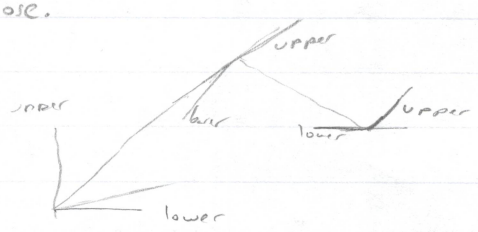
Vex Joystick Control





Functions:

CALIBRATION - ~~shoulder~~

shoulder - lift arm all the way up to perpendicular from ground - straight up, until the arm hits a bump switch or a limit switch, but movement should it be restricted if possible.

~~then goes down to its lower limit, counts~~

arm then goes down to its lower limit and counts the # of rotations / encoder degrees moved, and sets that equal to degree movement.

Do lower first, then upper.

at lower - set ~~current degrees~~ offset rotations = to current reading.

at upper - set maximum equal to current rotations minus offset rotations.

then - for calculate number of encoder steps per degree on that motor.

Making the code reusable:

[redacted] its relative

needs to know: the lower ~~calibrations~~ limit switches degrees from ~~that~~ origin

the upper limit switches degrees from relative origin, the ports for those buttons, the motor used, and the encoder used.

☆ TREAT MOTORS W/ IEM's as steppers! - make movements steps.