File: C:\Users\M4rc05\Documents\Vex\Starstruck\2223-G\4-5-2017\Autonomous Recording\AutonomousRecording.c

```
#pragma config(Sensor, dgtl1,  leftEncoder,    sensorQuadEncoder)
#pragma config(Sensor, dgtl3,  rightEncoder,   sensorQuadEncoder)
#pragma config(Motor,  port1,           RightMotor,    tmotorVex393 HBridge, PIDControl, driveRight, encoderPort, dgtl3)
#pragma config(Motor,  port10,          LeftMotor,     tmotorVex393_HBridge, PIDControl, reversed, driveLeft, encoderPort, dgtl1)
//*!!Code automatically generated by 'ROBOTC' configuration wizard               !!*//

short baseLeft[1000], baseRight[1000];
int threshold = 15, buttonToggleState = 0, buttonPressed = 0;

task main(){
  for(int c = 0; true;){
    if( vexRT[Btn8R]){
      if(!buttonPressed){
        buttonToggleState = 1 - buttonToggleState;
        buttonPressed = 1;
      }
    }
    else buttonPressed = 0;

    motor[LeftMotor] = (vexRT[Ch2]>threshold  || vexRT[Ch2]< -(threshold) || vexRT[Ch1]>threshold || vexRT[Ch1]< -(threshold))? (vexRT[Ch2] - vexRT
    motor[RightMotor] = (vexRT[Ch2]>threshold  || vexRT[Ch2]< -(threshold) || vexRT[Ch1]>threshold || vexRT[Ch1]< -(threshold)) ? (vexRT[Ch2] + vex

    if (buttonToggleState){
      c++;
      baseLeft[c] =  (vexRT[Ch2]>threshold  || vexRT[Ch2]< -(threshold) || vexRT[Ch1]>threshold || vexRT[Ch1]< -(threshold)) ? (vexRT[Ch2] - vexRT[
      baseRight[c] = (vexRT[Ch2]>threshold  || vexRT[Ch2]< -(threshold) || vexRT[Ch1]>threshold || vexRT[Ch1]< -(threshold)) ? (vexRT[Ch2] + vexRT[
    }
    if(vexRT[Btn7L] == 1){
      for(int d = 0; d < sizeof(baseLeft)/sizeof(short); d++){
        motor[LeftMotor] = baseLeft[d];
        motor[RightMotor] = baseRight[d];
        wait1Msec(20);
      }
    }
    wait1Msec(20);
  }
}
```