

File: C:\Users\M4rc05\Documents\Vex\Starstruck\2223-G\3-30-2017\DriverControl.c

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

int threshold = 15;

task main(){
    while(true){
        if(vexRT[Ch2]>threshold || vexRT[Ch2]< -(threshold) || vexRT[Ch1]>threshold || vexRT[Ch1]< -(threshold)){
            //make sure small movements of the joystick do not move the robot
            motor[LeftMotor] = (vexRT[Ch2] - vexRT[Ch1]);
            motor[RightMotor] = (vexRT[Ch2] + vexRT[Ch1]);
        }
        else{
            //if joystick values less than 15 and greater than -15 then stop the base's motors
            motor[LeftMotor] = 0;
            motor[RightMotor] = 0;
        }
    }
}
```

