

# FRC Programming

Team 1351

2019

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# **1 Overview**

This is team 1351s FRC programming documentation for the essential knowledge we use on this team. This covers motors and actuators (mostly Talons and Servos), sensors, controllers, pneumatics, the robot class, and command based programming.

## 2 Talons

### 2.1 What is a Talon

A Talon is a motor controller that allows to change the speed of the motor, which can be based on various different controlling methods. Each talon has a unique id between 0 - 63, so the code knows which talon to program when the code is executed.

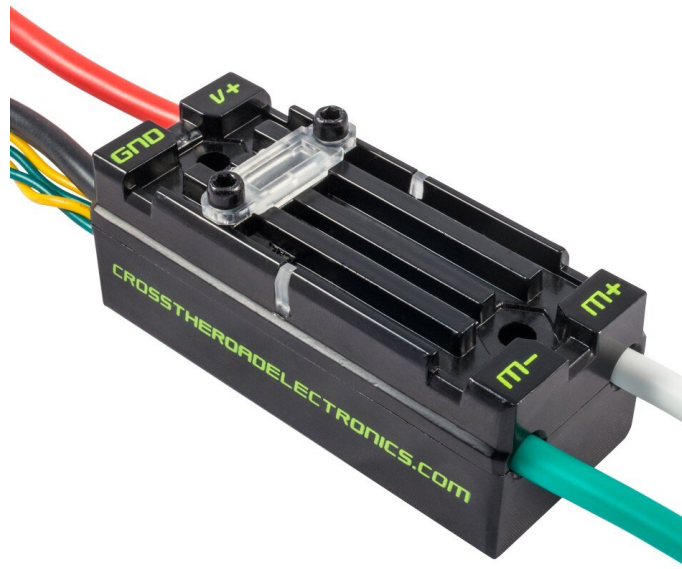


Figure 1: A picture of a talon

### 2.2 Configuring a Talon

#### 2.2.1 Constructing a Talon

When creating a talon, use the `WPI_TalonSRX` object.

```
WPI_TalonSRX talon;
```

The Talon Constructor only takes in 1 parameter: the id of the talon.

```
talon = new WPI_TalonSRX(0);
```

### 2.2.2 Configuring Talon Hardware

It is generally safe to configure every talon to the default setting before messing with anything else.

```
talon.configFactoryDefault();
```

Talons may be inverted in hardware, and you may need to invert them in code again.

```
talon.setInverted(true);
```

It can be also useful to limit the max speed. The code below limits the max speed of the motor to be 0.5 (percent output).

```
talon.configPeakOutputForward(0.5);
```

To set the max speed of the motor in the negative direction, use:

```
talon.configPeakOutputReverse(0.5);
```

You can also limit the current draw of a motor. The code below sets the maximum current draw 20 amps.

```
talon.configContinuousCurrentLimit(20);
```

Sensor hardware attached to the talon may also need to be configured (read Sensor for more info).

## 2.3 Control Modes

Talons have various different Control Modes that can be used to control the power of the motor. A Talon can control a motor with the set function.

```
talon.set(ControlMode.xxx, double value);
```

### 2.3.1 PercentOutput

PercentOutput sets the motor to go at a speed from range -1.0 to 1.0, and the actual speed of the motor is based on battery voltage multiplied by the input value. The code below sets the talon to go to 50%.

```
talon.set(ControlMode.PercentOutput, 0.5);
```

The default Control Mode is PercentOutput, so just inputting 0.5 will do the same thing.

```
talon.set(0.5);
```

### 2.3.2 Current

Current sets the motor to use a certain amperes to move the motor. The code below sets the motor to use 10 amps of current.

```
talon.set(ControlMode.Current, 10);
```

To make the motor spin in the opposite direction, just put a negative sign in front of input value

```
talon.set(ControlMode.Current, -10);
```

**Remember that this controls current.** The current draw of the robot depends on countless factors, and the current draw moving one way may be a different speeds as if you were moving the other way (especially if your are move with or against gravity).

### 2.3.3 Follower

Follower mode sets the talon to mimic the same talon with the inputted ID. This code sets the talon to mimic the talon with id 0.

```
talon.set(ControlMode.Follower, 0);
```

To make code less confusing, use the `getDeviceID()` function to make it clear which talon is being followed. The code below makes it obvious talon1 is following talon0.

```
talon1.set(ControlMode.Current, talon0.getDeviceID()  
());
```

### 2.3.4 Position

Position mode uses an encoder and PID to have to motor move to a certain position. The code below sets the talon to move 500 ticks (see Sensors for more info).

```
talon.set(ControlMode.Position, 500);
```

### 2.3.5 Velocity

Velocity mode uses an encoder and PID to have a motor move at a certain velocity. The code below sets the motor to a speed of 150 ticks / 100 ms (see Sensors for more info).

```
talon.set(ControlMode.Velocity, 150);
```

## 3 Other Motors / Actuators

### 3.1 Servos

#### 3.1.1 What is a Servo

A Servo is similar to a motor, but it only has 180 degrees of motion. The Servo is plugged into the PWM on the roborio, and the slot it is plugged into determines the id.



Figure 2: A picture of a servo

#### 3.1.2 Uses of Servos

Servos are useful in situations where you need a "mini motor" since they are a lot smaller. Of course, the job should not require more than 180 degrees of motion.

#### 3.1.3 Programming Servos

In order to program a servo a new Servo object must be created

```
Servo servo;
```

The Servo constructor takes in one parameter, the ID of the servo. The code below initializes a servo with ID 0.



```
servo = new Servo(0);
```

In order to set the angle of a servo, use the `setAngle()` function. The code below sets the servo to 90 degrees

```
servo.setAngle(90);
```

## 4 Sensors

### 4.1 What are sensors

Sensors return feedback that can be used in the code for several purposes, which includes controlling talons. There are hundreds of different sensors, but FRC uses three main ones. While the sensor values alone can be used to control motors or other actuators, they are generally combined with closed loop control (see section below for more info) to actually control the motors more accurately.

### 4.2 Switches

#### 4.2.1 What is a switch

A switch is a device that returns true or false, depending on whether it is pressed or not pressed. A switch can be wired either to the DIO port on the Roborio, or through a sensor wire connected to a talon.



Figure 3: A picture of a switch

#### 4.2.2 Uses of a Switch

A switch can be used for any of these reasons:

1. A limit switch, which is placed at the end of any mechanical system that stops something from moving past where it is supposed to.
2. To detect whether an object is present or not (such a frc game piece)
3. To reset an encoder (see Encoder for more info)

### 4.2.3 Switches through the roborio

If a switch is wired through the roborio, a new object needs to be created. This object is called a `DigitalInput`.

```
DigitalInput switch0; //switch is a key word in
java
```

Each switch plugged into the roborio has an id, and the id is determined based on which DIO slot it is plugged into. the constructor for `DigitalInput` takes one input, the id for the switch. The code below initializes the switch to have an id of 0.

```
switch0 = new DigitalInput(0);
```

To read the value of a switch, use the `get()` function

```
boolean isSwitchPressed = switch0.get();
```

### 4.2.4 Switches through the talon

If a switch is wired through the talon, then no new object needs to be created. Up to two switches can be wired to one talon. To get the value of the switch use `getSensorCollection()`.

```
talon.getSensorCollection().isFwdLimitSwitchClosed();
```

This returns if the switch is pressed. If you want to get the value of the other switch, use:

```
talon.getSensorCollection().isRevLimitSwitchClosed();
```

The switches that are wired up automatically act as limit switches, and no limit switch code is necessary if they are wired to the talon. **Make sure that the switch is not wired backwards.** Since this cannot be reversed in code, the switch **must** be wired electrically correct; otherwise, the limit switch code will be broken.

## 4.3 Encoders

### 4.3.1 What is an encoder

An encoder is a device that counts "ticks" and is attached to the talon. For each revolution of the motor, x amount of ticks pass (otherwise known as the CPR). This can differ based on what encoder is being used, but the CPR is generally 1000.

### 4.3.2 Uses of an encoder

An encoder has two main purposes. First, it tracks position of a motor. Position tracking is very useful, as there are countless cases where we want the robot to move to a certain position, or for a mechanism to be at a certain spot. Second, it is able to get a *near* instantaneous velocity of the motor. This can also be

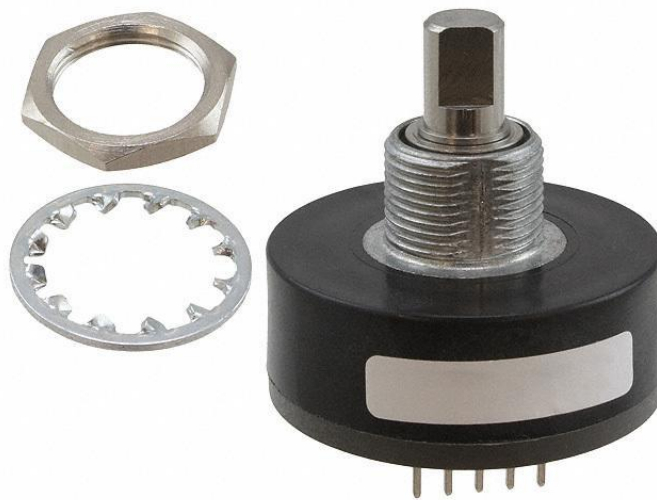


Figure 4: A picture of an encoder

very useful, as it attempts to compensate for outside factors when setting speed, which PercentOutput fails to do.

#### 4.3.3 Types of Encoders

There are two main types of encoders: Quad Encoders and Mag Encoders. Quad Encoders use mechanical ticks to count, making the more accurate but also more frail. Mag encoders use magnetic fields to count, making the less accurate but more durable. Generally, we use Quad Encoders on our team.

#### 4.3.4 Ticks Per Inch

Since the value that an encoder returns is in ticks, it is easier to create a ticks per inch conversion so we can have position in a meaningful unit. Since velocity is in ticks / 100ms, we can just use the same value multiplied by 10 for a conversion to inches / second. To get ticks per inch, you can do two methods.

1. Take the  $CPR * GearRatio / CircumferenceOfWheel$
2. Make the robot move a certain known distance in inches, find how many ticks was traveled in the process, and your ticks per inch is  $ticks/inches$  (less accurate, but gear ratio is a hard number to get)

### 4.3.5 Programming an encoder

An encoder must be configured through the talon. Use the `configSelectedFeedbackSensor()` function to do this.

```
talon.configSelectedFeedbackSensor(FeedbackDevice.  
    QuadEncoder);
```

If you wanted to use a Mag Encoder, you would use `FeedbackDevice.CTRE_MagEncoder_Absolute` or `FeedbackDevice.CTRE_MagEncoder_Relative` (I won't go over the differences here). To get the current position of the encoder, use:

```
talon.getSelectedSensorPosition();
```

To get it in readable units, use the calculated ticks per inch value to convert. Since the encoder position is scrambled every time the robot is powered off and on again, it is important to be able to reset the encoder if you need position (not distance). Generally, a limit switch is used to reset the encoder (0 is where the switch is located). To reset the encoder, use `setSelectedSensorPosition()`. The code below sets the encoder value to 0.

```
talon.setSelectedSensorPosition(0);
```

When using an encoder to make the robot move, `ControlMode.Position` and `ControlMode.Velocity` are generally used. However, both of these use PID control in order to work. (see PID below).

## 4.4 Gyro

### 4.4.1 What is a Gyro

A gyro is a sensor measures the angle of the robot. It however does not read between 0 - 360, if the robot turns one full cycle and then another 90 degrees, the gyro will return 450, not 90. Clockwise is positive, counterclockwise is negative.

### 4.4.2 Uses of a gyro

Knowing the angle of the robot is very useful for autonomous, as the angle of the robot is necessary in order to turn the robot without driver input.

### 4.4.3 Programming a gyro

In order to use a gyro, a new Gyro object must be created.

```
ADXRS450-Gyro gyro;
```

The constructor for the Gyro does not require any inputs, as only one gyro can be on a robot.

```
gyro = new ADXRS450-Gyro();
```

To get the current angle of the gyro, use the `getAngle()` function

```
double robotAngle = gyro.getAngle();
```

When moving using the Gyro, a PID loop is usually used to control the robot (see PID below)

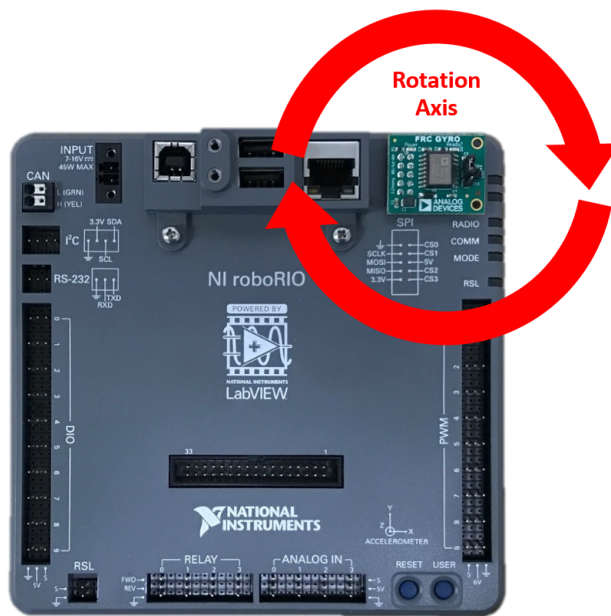


Figure 5: A picture of a gyroscope

## 5 Closed Loop Control

### 5.1 What is Closed Loop Control

Closed Loop control requires using feedback from sensors in a continuous loop to accurately move the motor to a certain position or velocity.

#### 5.1.1 Types of Closed Loop Control

While there are several types of closed loop control used, the two main ones used in robotics are bang-bang control and PID control.

### 5.2 Bang-bang control

#### 5.2.1 What is Bang-bang control

Bang bang control is very simple to write and easier to tune, but less accurate than PID control. It follows a very simple rule: Go forward if you are behind, and go backward if you are ahead. Bang bang just runs at the same speed or acceleration (based on if you are running position or velocity mode), just moving in a different direction. Basic bang-code would look like this (pseudo code):

```
while(!inTreshold){
    if(currentPos < desiredPos){
        setTalonSpeed(speed);
    } else if(currentPos > desiredPos){
        setTalonSpeed(-speed);
    } else {
        setTalonSpeed(0);
        inTreshold = true;
    }
}
```

In the pseudo code below, the loop goes until the position matches the desired position. The speed of the motor is set to a constant value called "speed".

#### 5.2.2 Thresholding

Since it is nearly impossible to actually get to the exact desired position, a threshold is used. The threshold is basically a range that the loop is allowed to be in for the loop to end, so the loop can actually end in a reasonable amount of time. This is pseudo code of bang-bang control with thresholding in place.

```
while(!inTreshold){
    if(desiredPos - currentPos > threshold){
        setTalonSpeed(speed);
    } else if(currentPos - desiredPos < -threshold){
        setTalonSpeed(-speed);
    } else {
        setTalonSpeed(0);
        inTreshold = true;
    }
}
```

### 5.2.3 Timing

While having a threshold is useful, it is also important to make sure the robot stays in that threshold for a certain amount of time. This can be done by either counting the amount of loop times that have passed or seeing if the amount of time spent in the loop is greater than a number. The code below does this with checking the number of loop times that have passed.

```
while(count < 5){
    if(desiredPos - currentPos > threshold){
        setTalonSpeed(speed);
        count = 0;
    } else if(currentPos - desiredPos < -threshold)
    {
        setTalonSpeed(-speed);
        count = 0;
    } else {
        setTalonSpeed(0);
        count++;
    }
}
```

## 5.3 PID Control

PID Control, while more difficult to write and tune, can be a lot more accurate is done correctly. PID Control uses three variables (P, I, and D) and feedback from a sensor to determine motor speeds.

### 5.3.1 Programming a PID Controller

There are a few different ways to write up PID code, but the main method to write PID is using the PIDController object.

```
PIDController pidController;
```

The PIDController constructor has five different parameters: the first three represent the p, i, and d values, the fourth parameter is the input source (the sensor), and the fifth parameter is the output source (a motor controller). In the example below, a new PIDController is being constructed with pid values of 0.2, 0, 0.1, it is programmed to use the gyro as the sensor, and the leftTalon to be the output source

```
pidController = new PIDController(0.2, 0, 0.1, gyro
, leftTalon);
```

Often times, it can be useful to not have an output source but still run the controller (especially if you are trying to integrate two PID loops), so a "dummy output" can be made. A PIDOutput object needs to be created, and the constructor will use that object for the output source, so the loop runs without controlling any motor directly.

```
PIDOutput dummyOutput = output -> {
```



```
};
pidController = new PIDController(0.2, 0, 0.1, gyro
    , dummyOutput);
```

After initializing the PID controller, there are several configurations that can be placed on the loop. If you want to set a maximum output that the control loop can produce, use the `setOutputRange()` function. The code below sets the output range that the PIDController can produce to be between -0.8 to 0.5 (Usually, the negative and positive number are the same).

```
pidController.setOutputRange(-0.8, 0.5);
```

**The lowest output that can be set is -1.0, and the highest output that can be set is 1.0.** If you want to limit the range that the setpoint can be set to, use the function `setInputRange()`. The code below restricts the input setpoint to be between 0 and 360.

```
pidController.setInputRange(0, 360);
```

In situations where the robot may be taking the long route to get to where it needs to be (ex: 270 left instead of 90 right), the `setContinuous()` function can be useful. By enabling this setting, the min and max input range is considered the same value, and the shortest route to they desired position is calculated based on that.

```
pidController.setContinuous(true);
```

**You need to have `setInputRange()` before `setContinuous()`.** Furthermore, this function can cause errors when run in commands (see command based programming for more info). To set the setpoint of the PID loop, use the `setSetpoint` function. The code below sets the setpoint to 180.

```
pidController.setSetpoint(180);
```

In order for the PIDController to actually be run, the `enable()` function needs to be called.

```
pidController.enable();
```

Regardless of whether you are using a "dummy output" or an actual output source, knowing the speed that the PID controller is setting can be very useful. Use the `get()` function to get that speed, on a scale from -1.0 to 1.0 (or the output range if that is configured).

```
double output = pidController.get();
```

### 5.3.2 Programming Talon PID

When using PID with a talon and an encoder, using the `ctre talon` classes should be used instead of the `PIDController` classes. Instead of an object being created, the PID configurations should be set through the talon. TO set the P, I, and D values, use the `config_kP` (use `kI` or `kD` for I and D) to set the PID values. The code below configures the  $P = 0.2$ ,  $I = 0.01$ , and  $D = 0.1$ .

```
talon.config_kP(0.2);
talon.config_kI(0.01);
talon.config_kD(0.1);
```

If you want to cap the maximum output of the PID loop, use the `configClosedLoopPeakOutput()` function instead. The code below sets the maximum closed loop output to 0.3.

```
talon.configClosedLoopPeakOutput(0.3);
```

This function sets the range to between -0.3 to 0.3 (you cannot make the minimum different than the maximum, although that is generally not necessary.) The talon has two main PID modes to be used: Position and Velocity. The position mode sets the talon to go to a certain position (in ticks), and the velocity mode sets the wheels to go at a certain velocity (in ticks / 100ms).

```
talon.set(ControlMode.Position, 1000);
talon.set(ControlMode.Velocity, 200);
```

The position code sets the talon to move to a position where the encoder reads 1000. The velocity code sets the talon to go at a speed where it travels at 200 ticks / 100ms. The `TicksPerInch` value (read Encoders to get more information) can be used to track the position in inches or in inches per second, so the input can be more realistic to the user.

### Ramping position

It is important to ramp your value, since if you try to set PID to go directly to the position you are attempting to reach, the PID can go out of control. There are several different ways to ramp your position, but one way would be to set your temporary setpoint to your current position plus a certain ramp rate until you get your position within the ramp rate.

### 5.3.3 Tuning PID

Tuning PID, while annoying, can lead to incredible accuracy if done well.

#### What P, I, and D control

P, I, and D each control the robot in different ways. P is a simple constant proportion: the bigger to speed, the faster the robot moves. I causes an increase of speed over time: the longer the loop is running, the faster the robot will go. A little bit of I can be useful to make a system run faster, but too much can cause the system to overshoot and go haywire. Lastly, D slows down the system when the robot is going is moving too fast. However, too much of D can cause the robot to jitter.

#### Ziegler-Nichols

The Ziegler-Nichols method is a very mathematical method to tune PID. First, set the P value at an arbitrarily low number, and I and D to 0. Then increase the P value until you have a stable oscillation (rocks back and forth around setpoint). If the P value is too low, it will undershoot. If the P value is too high, then the robot will have unstable oscillation (each rock goes farther and farther away from the setp int. After getting this value, set a variable called K to that value. Afterwards, time the amount of time it takes for one oscillation

and label that variable T. Then, follow these formulas to determine your P, I, and D values.

$$P = K/2$$

$$I = 1.2K/T$$

$$D = 3KT/40$$

These values usually will not work first try, but based on what P, I, and D do, you can increase or reduce values to tune the control system.

### **Experimental Tuning**

If you are in a time crunch and do not have the time to do the whole Ziegler-Nichols method, a quick, but not quite as precise, method can be used. Similar to Ziegler-Nichols, find the P value where steady oscillation exists. Afterwards, set your D value to be 10x of your P. Afterwards, you can tune your P and D values according to how the system behaves. This method may run slower because it avoids using I altogether, but it can be useful in a time crunch.

## 6 Controllers

### 6.1 What is a controller

A controller is something that takes in user input through driver station and uses that to control the robot. Examples include joysticks and xbox controllers.

### 6.2 Digital Input

A digital input returns either true or false, such as a button press.

#### 6.2.1 Get Button

any `getButton_()` function returns true if the button is pressed, and false if it is not pressed.

#### 6.2.2 Get Button Pressed

any `getButton_Pressed()` function will return true if the button goes from not pressed to pressed, and will otherwise return false. This function will return true only one time when the button is pressed, while `getButton_()` will continuously return true while it is being held down.

#### 6.2.3 Get Button Released

any `getButton_Released()` function will return true only when the button transitions from being pressed to being not pressed.

### 6.3 Analog Input

An analog input returns some number value, which can be used to determine more detailed control over the robot, rather than a simple yes or no. An example of an analog input is any joystick. Analog inputs are generally on a scale of -1.0 to 1.0.

### 6.4 The Joystick Class

The Joystick Class has all the controls needed for a Logitech Attack 3 Joystick, which is just a standard gaming joystick.

#### 6.4.1 Initializing the Joystick

To use the joystick, a new Joystick object must be created

```
Joystick joystick;
```

The joystick constructor has one parameter for ID, which can be configured in driver station. The code below configures a joystick with id 0

```
joystick = new Joystick(0);
```



Figure 6: A picture of the logitech attack 3

#### 6.4.2 Digital Input

The joystick has a trigger and 10 other buttons labeled from button 2 - 11. To get the trigger, use:

```
joystick.getTrigger();  
joystick.getTriggerPressed();  
joystick.getTriggerReleased();
```

To get any of the buttons, use the `getRawButton()` function. The code below gets the value of button 2

```
joystick.getRawButton(2);  
joystick.getRawButtonPressed(2);  
joystick.getRawButtonReleased(2);
```

#### 6.4.3 Analog Input

The joystick class has two analog inputs: the x-axis and the y-axis of the joystick. Both of them go between -1.0 to 1.0. The code below gets the value of the x and y-axis

```
joystick.getX();  
joystick.getY();
```

## 6.5 The XboxController Class

The Xbox Controller class is a class built for a standard Xbox Controller.



Figure 7: A Xbox Controller

### 6.5.1 Initializing the Joystick

Like the joystick, a `XboxController` object must be created.

```
XboxController controller;
```

The `xboxcontroller` constructor also has one parameter for ID. The code below configures a `xboxcontroller` with id 0.

```
XboxController = new XboxController(0);
```

### 6.5.2 Digital Input

The Xbox Controller has many sources of digital inputs, including both A, B, X, Y buttons, bumpers, and the D-pad. The code below checks for the A, B, X, and Y buttons.

```
controller.getAButton();  
controller.getBButton();  
controller.getXButton();  
controller.getYButton();
```

Both bumpers use the `getBumper()` function, so in order to differentiate between left and right, you have an input of left or right in the functions. The code below shows the right way to get the left and right bumpers.

```
controller.getBumper(GenericHID.Hand.kLeft);
controller.getBumper(GenericHID.Hand.kRight);
```

In order to get the D-pad value, the `getPOV()` function returns an integer of the degrees the D-pad is facing (0 for up, 90 for right, etc.) The function returns -1 if none of the D-pad is pressed.

```
controller.getPOV();
```

### 6.5.3 Analog Input

Since the Xbox Controller has two joysticks, the same input to determine left or right bumper is also used to determine the joystick. Each joystick has an X and Y value between -1.0 to 1.0

```
controller.getX(GenericHID.Hand.kLeft);
controller.getX(GenericHID.Hand.kRight);
```

The Xbox Controller also has two triggers, each goign from a value between 0 and 1.0

```
controller.getTriggerAxis(GenericHID.Hand.kLeft);
controller.getTriggerAxis(GenericHID.Hand.kRight);
```

## 6.6 The GenericHID Class

Both the Joystick and the XboxController Class are based on the GenericHID Class. This is basically the master controller class. If you want to create a new controller class for a type of controller a class doesn't exist for, use this class. The class has five main functions

```
getRawAxis(int id) //gets the value of the axis with
that id
getRawButton(int id) //gets the value of button with
that id
getRawButtonPressed(int id) //see Digital Input for
difference
getRawButtonReleased(int id) //see Digital Input for
difference
getPOV() //see XboxController for more info
```

## 7 Pneumatics

### 7.1 What is pneumatics

Pneumatics is a control system that uses pressurized air to control pistons, instead of using motors. While a pneumatics system comprises of many different components, the only components that need to be programmed are the compressor and solenoids.

### 7.2 The Compressor Class

#### 7.2.1 What is a compressor

A compressor is what pressurizes all of the air that is used in pneumatics system.



Figure 8: A picture of a compressor

#### 7.2.2 Programming a compressor

In order to run the compressor, a new compressor object must be declared.

```
Compressor compressor;
```



The Compressor constructor takes in no parameters, as only one compressor is allowed on each robot

```
compressor = new Compressor();
```

To start the compressor, use the start() function

```
compressor.start();
```

This is usually run in robotInit() (see The Robot Class for more info). In order to stop the compressor, use the stop() function.

```
compressor.stop();
```

If you find that the compressor is losing PSI, try using the setClosedLoopControl() function.

```
compressor.setClosedLoopControl(true);
```

**This is not a substitute for fixing a pneumatics system.** This function, while useful, will not completely nullify a leak, and it is not advised to start pressurizing in the middle of a match, which is what this function will do.

## 7.3 Solenoids

### 7.3.1 What is a solenoid

A solenoid is what controls a piston. A single solenoid can push a piston in one direction, while a double solenoid can control a piston to go in both directions. On our team, we mostly use double solenoids.

### 7.3.2 Programming single solenoids

To use a single solenoid, a Solenoid object must be created.

```
Solenoid solenoid;
```

The Solenoid constructor has one parameter for the solenoid channel (aka the ID). The code below creates a new solenoid with channel set as 0.

```
solenoid = new Solenoid(0);
```

In order to actuate the solenoid, use the set function.

```
solenoid.set(true);
```

**Setting the solenoid to false does not put pressure in the other direction.** Since it is a single solenoid, it either applies air pressure in one direction or does not apply air pressure at all.

### 7.3.3 Programming double solenoids

To use a double solenoid, a DoubleSolenoid object must be created.

```
DoubleSolenoid doubleSolenoid;
```

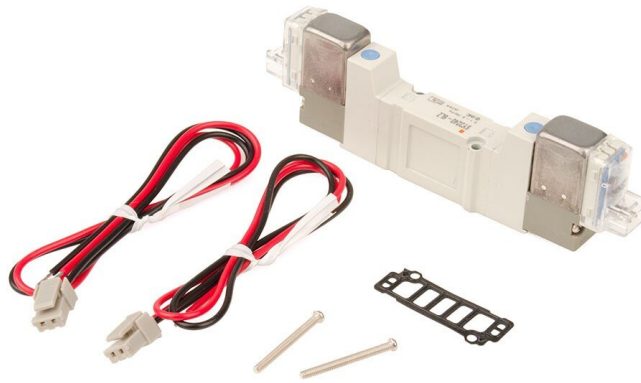


Figure 9: A double solenoid

The double solenoid constructor has two parameters, both being the two channels the solenoid uses (1 channel for each direction it applies air pressure). The code below creates double solenoids with channels 0 and 1.

```
doubleSolenoid = new DoubleSolenoid(0, 1);
```

In order to set the direction of the solenoid, use the `set()` function.

```
doubleSolenoid.set(DoubleSolenoid.Value.kForward);
```

The code above sets the solenoid to apply air pressure in the forward channel direction. To apply air pressure in the reverse channel direction (generally the opposite direction), use the `kReverse` enum.

```
doubleSolenoid.set(DoubleSolenoid.Value.kReverse);
```

If you want to set the solenoid to not apply air pressure, use the `kOff` enum.

```
doubleSolenoid.set(DoubleSolenoid.Value.kOff);
```

## 8 The Robot Class

### 8.1 What is the Robot Class

The Robot Class is the main file that your code is setup in. It contains various functions that allow for the control of the robot.

### 8.2 Types of Main Classes

#### 8.2.1 Sample Robot

Sample Robot is a good class to write up test code for prototypes or small tasks such as that. However, it should not be used for proper robot projects, as there is no loop timing in Sample Robot.

#### 8.2.2 Timed Robot

Timed Robot is the recommended class for most projects. It contains a changeable loop time, as well as initialize and periodic functions for all of the different modes.

#### 8.2.3 Iterative Robot

Iterative Robot is an older version of Timed Robot that is now deprecated. Timed Robot is recommended over this.

### 8.3 Robot

#### 8.3.1 Robot Init

The function `robotInit()` is where all of the hardware initialization should be located. It is also where all subsystems should be initialized (see Command Based Programming for more info).

#### 8.3.2 Robot Periodic

`robotPeriodic()` is where anything that should be running regardless of which mode the robot is in is ran. Usually, only Scheduler is run here (see Command Based Programming for more info)

### 8.4 Autonomous

The Autonomous functions run for during the first 15 seconds of a match, and usually ban driver control (exception of Deep Space).

#### **8.4.1 Autonomous Init**

`autonomousInit()` runs once right after the match starts. Usually, any commands or command groups specific to the autonomous period get initialized here.

#### **8.4.2 Autonomous Periodic**

`autonomousPeriodic()` runs continuously during the autonomous period of a match. Generally, nothing is needed to be run here.

### **8.5 Teleop**

The Teleop functions run from after Autonomous ends to the end of the match.

#### **8.5.1 Teleop Init**

`teleopInit()` runs once after the autonomous periods end. Generally, any autonomous commands get cancelled here if they are not already finished (see Command Based Programming for more info)

#### **8.5.2 Teleop Periodic**

`teleopPeriodic()` runs continuously during the entire match, except for the first 15 seconds. If you are not using Command Based Programming, this is where your controls should be setup.

### **8.6 Test**

Test is not run during a match, but these functions are good for seeing is pieces of code will work without editing your main code.

#### **8.6.1 Test Init**

`testInit()` runs once every time the robot is enabled in test mode. Can also be used as an area to store reset encoder functions for before a match starts.

#### **8.6.2 Test Periodic**

`testPeriodic()` runs continuously while the robot is enabled on test mode.

## 9 Command Based Programming

### 9.1 What is Command Based Programming

Command Based Programming is a structure of programming that organizes code to run based on loop times and deals with running multiple tasks at the same time for you. It is recommended to create any complex code using Command Based Programming.

#### 9.1.1 Parts of Command Based Programming

Command Based Programming involves 3 main parts: subsystem classes, command classes, and the OI class.

Each subsystem class is created for any one set of motor / pneumatics controllers.

Each command class is designated to run on a certain subsystem class, and they execute tasks using functions written in the subsystem class.

Lastly, there is the OI class, which initializes a controllers attached to driver station and sets up when commands should be executed based on controller input.

### 9.2 Subsystems

#### 9.2.1 How to differentiate subsystems

Before programming any subsystem, you need to know how to determine the amount of subsystems needed in the code, which is more complicated than it might seem at first. Remember, each subsystem runs on its own thread, so any two commands that want to be run simultaneously should be on different subsystems.

Lets use an ball intake as an example. While this constitutes as one mechanical subsystem, it may not be the same in code. An intake generally has two parts: rollers to take the ball in and motors to change the position of the intake. While this may not always be true, having the ability to intake a ball and change the position of the intake at the same time can be useful, so they would constitute as two separate subsystems.

Lets use a drive train as another example. While it is obvious the left and right side of the robot should both be able to move at the same time, it would still constitute as a subsystem most of the time (again, there can be exceptions to this). This is because there is generally no command that involves controlling one side and not the other, so having two separate subsystems is not necessary. While on the intake, there are situations where you would run the rollers and

change the position either separately or simultaneously, which is why they are separate subsystems.

### 9.2.2 Creating a subsystem

To create a subsystem, a new class must be created that extends the subsystem class, since the subsystem class is an abstract class.

```
public class DriveTrain extends Subsystem {  
  
}
```

### 9.2.3 Making a Singleton

Since each subsystem class that gets called only needs to be initialized once (I hope you don't have two different drive trains on the same robot), a singleton can be used. A singleton basically converts the class into a single instance, and in order to call any other functions in that class, you have to use the getInstance() method to access the one instance. The code below converts the DriveTrain class into a singleton

```
private static DriveTrain ourInstance = new  
    DriveTrain();  
public static DriveTrain getInstance() {  
    return ourInstance;  
}  
private DriveTrain() {  
    super("DriveTrain");  
}
```

Since the constructor is made private, and the only instance of the class is within the DriveTrain class, only the getInstance() method can be used to get the only instance of the class. The super("DriveTrain") is calling the constructor from the subsystem class, and the parameter is just the name of the subsystem.

### 9.2.4 The Init Hardware function

To initialize all of the hardware used in the subsystem, create an initHardware() function and call that function in robotInit(). The code below initialized two talons

```
WPI.TalonSRX leftTalon , rightTalon;  
public void initHardware(){  
    leftTalon = new WPI.TalonSRX(0);  
    leftTalon.configFactoryDefault();  
    leftTalon.setInverted(true);  
    rightTalon = new WPI.TalonSRX(1);  
    rightTalon.configFactoryDefault();  
}
```

### 9.2.5 The Init Default Function

When the subsystem class is extended, it requires you to add a function called `initDefaultCommand()`. This is used to set a default command, which is run whenever no other command is set to run on the subsystem (see Commands for more info). To set the default command, use the `setDefaultCommand()` function. the code below sets the default command of drivetrain to the tank drive command.

```
@Override
public void initDefaultCommand() {
    setDefaultCommand(new TankDrive());
}
```

**The default command is optional.** If you do not want to set a default command, just leave the `initDefaultCommand()` function empty, but you must have it within your class.

## 9.3 The OI Class

The OI class is used to actually control the robot through driver station through commands. There are two ways to control commands: either use the button class for digital inputs or accessing joystick values for analog input.

### 9.3.1 Configuring the OI class

Since there is only one OI class that is needed, the OI class is turned into a singleton like each of the subsystem classes are.

```
private static OI ourInstance = new OI();
public static OI getInstance() {
    return ourInstance;
}
private OI() {
}
```

Inside the OI class, each of the controllers should be declared privately and accessed through a function. The example below as a XboxController and a Joystick

```
XboxController controller;
Joystick joystick;
public XboxController getController(){
    if(controller == null){
        controller = new XboxController(0);
    }
    return controller;
}
public Joystick getJoystick(){
    if(joystick == null){
        joystick = new Joystick(1);
    }
    return joystick;
}
```

In the code below, the joysticks get initialized after the first time that they are called.

### 9.3.2 Digital Inputs

In order to use digital inputs, a Button object must be created. The code below creates a button object with the xbox controller A button.

```
Button aButton = new Button() {  
    @Override  
    public boolean get() {  
        return getController().getAButton();  
    }  
};
```

After creating a button, you can use one of the following functions to control when a command executes.

```
whenPressed();  
whenReleased();  
whileHeld();
```

These functions run either when a button is pressed, released, or while held (look at digital inputs in controllers for more info). The code below will run the GearShift command when the a button is pressed.

```
aButton.whenPressed(new GearShift());
```

### 9.3.3 Analog Inputs

To use analog inputs, use the OI class functions that access the controllers and use those values in the command itself.

## 9.4 Commands

Each command has various different parts that allow for control of the subsystem.

### 9.4.1 The constructor

Each subsystem should have a constructor, and the constructor should have the following parts: naming the command using super("Name"), parameters (if necessary), and the requires() function, which sets the command to run on the inputted subsystem. Below is an example constructor for Gear Shifting.

```
public GearShift(boolean shiftHigh){  
    super("GearShift");  
    this.shiftHigh = shiftHigh;  
    requires(Shifter.getInstance());  
}
```



In this example, the constructor has a super to name the command, and the parameter value is set to a local variable, and the command is set to require the Shifter subsystem (Shifter.getInstance() gets the only instance of the Shifter subsystem).

#### 9.4.2 The Initialize function

Every command can have the initialize() function, which runs one time after the command is started. Anything that needs to be run just once at the beginning of the command (variable initialization w/o parameters, solenoid shifting, etc.). In the code below the solenoid shifts based on the shiftHigh boolean.

```
@Override
protected void initialize(){
    if(shiftHigh){
        DriveTrain.getInstance().shiftHigh();
    } else {
        DriveTrain.getInstance().shiftLow();
    }
}
```

#### 9.4.3 The Execute function

The execute() function runs once every loop cycle until either the command is finished or the isFinished() boolean returns true (see is finished function for more info). Anything that needs to be constantly run with just slight variation should be put in the execute function. Below is tank drive code put in the execute function for a tank drive command.

```
@Override
protected void execute(){
    double left = OI.getInstance().getController().
        getY(
            GenericHID.Hand.kLeft);
    double right = OI.getInstance().getController().
        getY(
            GenericHID.Hand.kRight);
    DriveTrain.getInstance().tankDrive(left, right);
}
```

The code below sets tankDrive using the x and y values of the xbox controller. While the code may look a bit convoluted, it is really just taking advantage of the singleton system, and the code would involve a lot of static variables otherwise, which can get pretty messy. Also, the code demonstrates how to using analog input with commands and subsystems works.

#### 9.4.4 The Is Finished function

This function returns a boolean to check if the execute function should end or not, and it is **mandatory** to have whenever the command class is extended. Think of the way isFinished() works like this:

```

while (!isFinished()) {
    execute();
}

```

The code below is an example isFinished function for the tank drive command.

```

@Override
protected boolean isFinished() {
    double left = OI.getInstance().getController().
        getY(GenericHID.Hand.kLeft);
    double right = OI.getInstance().getController().
        getY(GenericHID.Hand.kLeft);
    return Math.abs(left) < 0.05 && Math.abs(right)
        < 0.05;
}

```

The code returns true only when both joysticks are under the threshold value, which is when the command is supposed to end. **Commands can simply return true or false.** If a command is set as the default command, it can return false and just get overridden by other commands (a TankDrive command may do this). A command can also just return true if nothing needs to be run in execute (such as a gear shift command).

#### 9.4.5 The End function

The end() function runs once right after the execute function stops looping (aka isFinished returns true). This can be useful, especially for stopping motors after a command is finished or running another command that needs to always follow the current command. The code below is example code for a TankDrive commands end() function.

```

@Override
protected void end() {
    DriveTrain.getInstance().tankDrive(0, 0);
}

```

This code sets the drive train to stop moving after the command finishes.

#### 9.4.6 The Interrupted function

This command runs if the execute function is interrupted (by calling another command on the same subsystem or just by stopping a command). Generally, the same code that goes into end() goes into interrupted(), but if necessary, two different tasks can be performed in each case. The code below is an example interrupted() function.

```

@Override
protected void interrupted() {
    end();
}

```

In this code, the interrupted function is just set to run the same code as run (stop the drive train from moving) since no special task needs to be run if the command is interrupted.

## 9.5 Scheduler

The Scheduler class is a class provided in the frc libraries that controls when commands actually get executed. The details on how that works are explained in official frc docs, but basically, the command `Scheduler.getInstance().run()` needs to be called in all periodic functions if commands are being used in those functions. You can also just be Scheduler inside `robotPeriodic()` if you need it in autonomous, teleop, and test. The code below demonstrates this:

```
@Override
public void robotPeriodic() {
    Scheduler.getInstance().run();
}
```