

Autonomous Independent.vi  
C:\Users\dogg\Documents\GitHub\RAN2023\2024RobotCode\2024StateMachineDevelopment\  
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## Autonomous Independent.vi



This VI is called when autonomous begins, and will automatically be terminated when autonomous ends. You can carry out timed or sensor driven robot movement independently without needing to return to the caller.

Array of robot movements

0

X Joystick Value	Y Joystick Value	Delay (sec)	Movement Name
			turn
			turn back

Be sure to right-click and choose Data Operations>>Make Current Value default if you want to save the array values with the VI

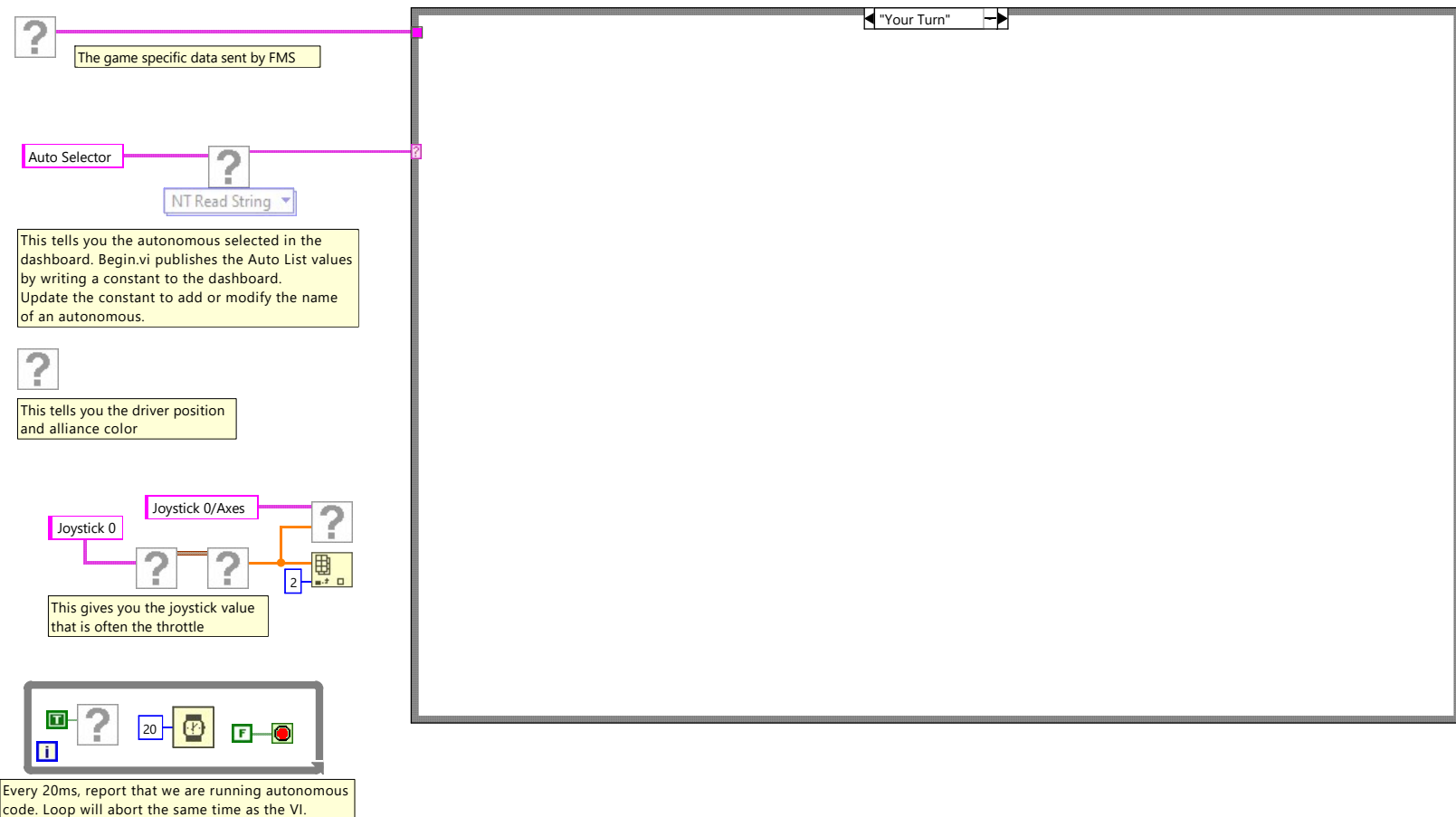
### Current Movement, for debugging

X Joystick Value	Y Joystick Value	Delay (sec)	Movement Name

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Note that all Driver Station inputs are automatically latched and will not change once auto begins.

Use time and/or sensors to control how the robot drives.



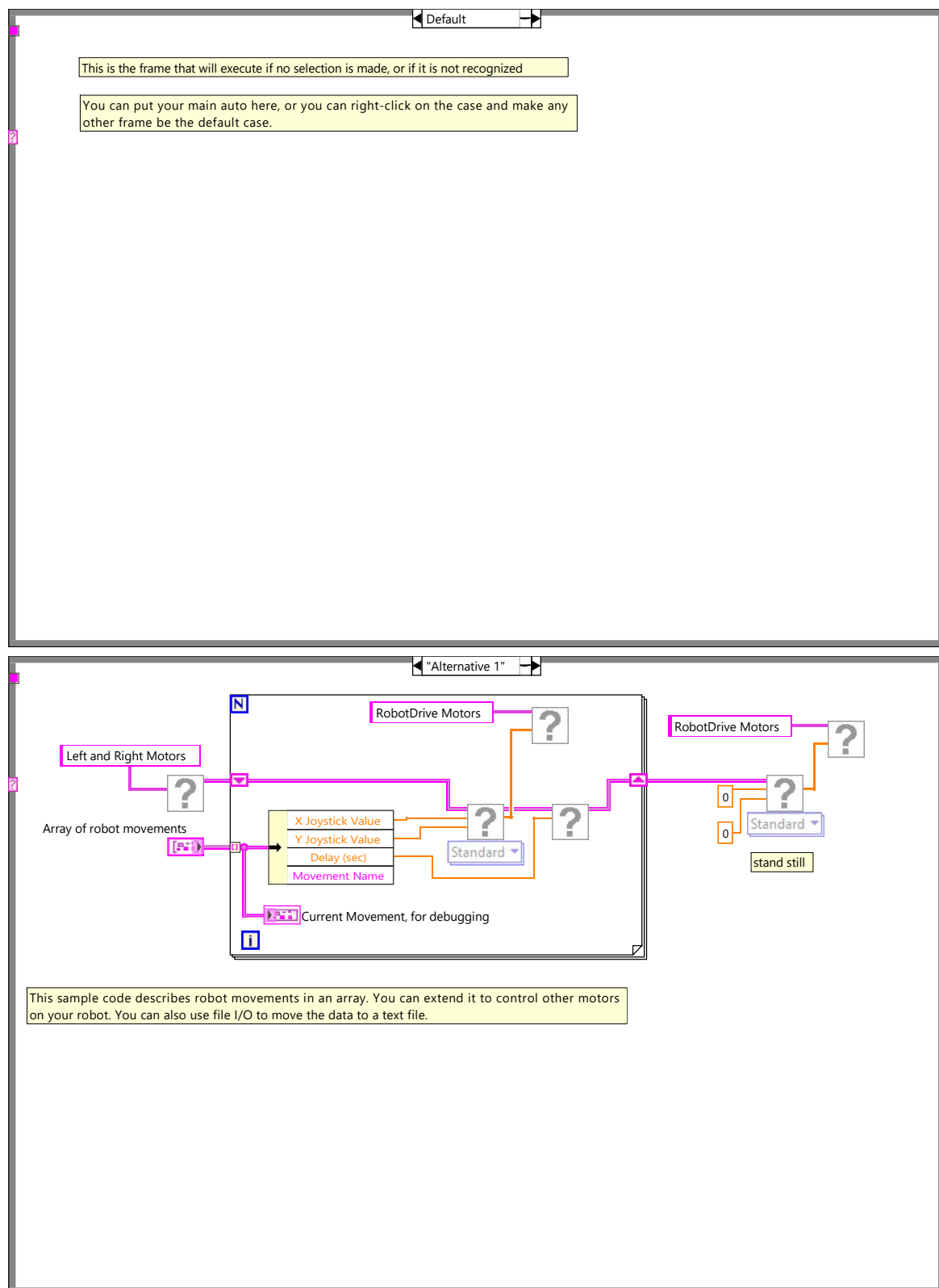
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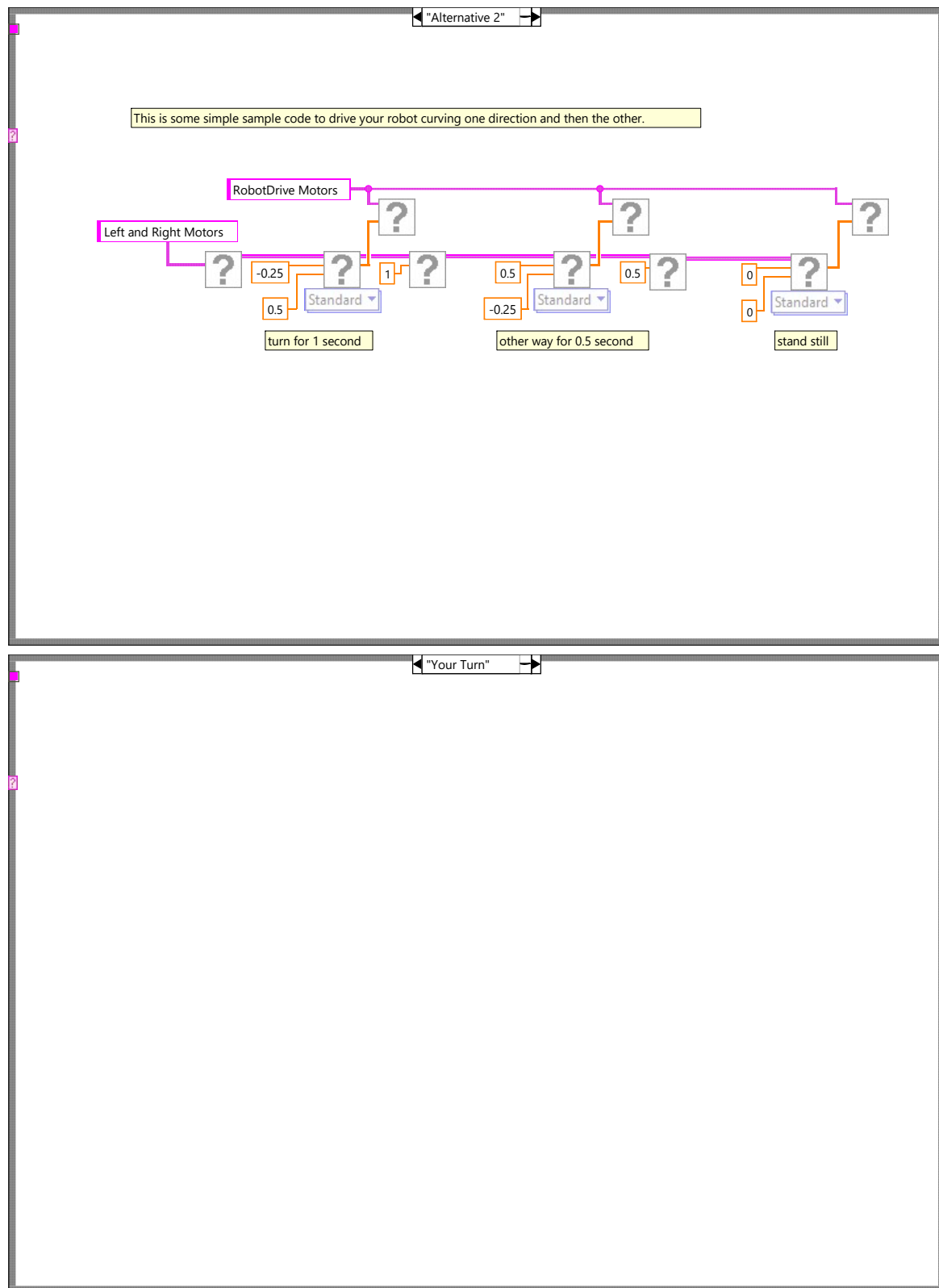
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