

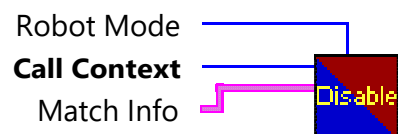
Disabled.vi

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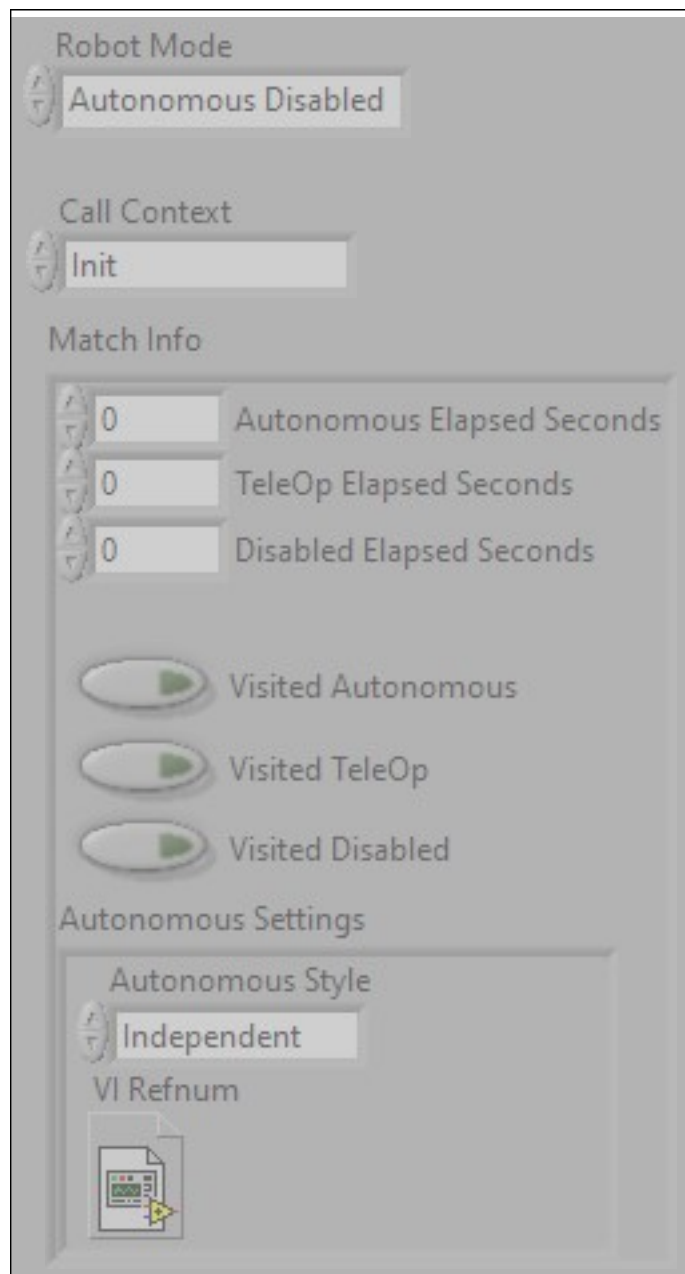
Disabled.vi

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**Disabled.vi**

This VI is called each time a disabled packet is received from the DS. It is often used to prepare for the next robot mode, to calibrate sensors, etc.

**Call Context**

<B>Derived Robot State</B> returns the allowed derived robot state for the current phase of competition. Options include <B>Init</B>, <B>Execute</B>, and <B>Stop</B>.



Disabled.vi  
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**Robot Mode**

<B>Robot Mode</B> returns the allowed robot mode for the rules of the current phase of competition. Options include <B>Autonomous Disabled</B>, <B>Autonomous Enabled</B>, <B>Teleop Disabled</B>, and <B>Teleop Enabled.</B>



**Match Info**



**Autonomous Elapsed Seconds**



**TeleOp Elapsed Seconds**



**Disabled Elapsed Seconds**



**Visited Autonomous**



**Visited TeleOp**



**Visited Disabled**



**Autonomous Settings**



**Autonomous Style**



**VI Refnum**

Disabled.vi

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This VI is called each time a disabled DS packet is received.

Typically nothing is done in response, but you may decide to calibrate sensors or camera. You could also choose to zero actuators or control loops to avoid glitches when the outputs are enabled again.

### Match Info



This can help determine what has been run and for how long

### Call Context



Use to differentiate between First, Last, and Intermediate calls

### Robot Mode



Use to differentiate between Auto and TeleOp Disable

Each time we enter, report that we are disabled

