# RIT VEXU Core API

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# Chapter 1

# Core

This is the host repository for the custom VEX libraries used by the RIT VEXU team

Automatically updated documentation is available at here. There is also a downloadable reference manual.

## 1.1 Getting Started

In order to simply use this repo, you can either clone it into your VEXcode project folder, or download the .zip and place it into a core/ subfolder. Then follow the instructions for setting up compilation at Wiki/BuildSystem

If you wish to contribute, follow the instructions at Wiki/ProjectSetup

## 1.2 Features

Here is the current feature list this repo provides:

Subsystems (See Wiki/Subsystems):

- Tank drivetrain (user control / autonomous)
- Mecanum drivetrain (user control / autonomous)
- Odometry
- Flywheel
- Lift
- Custom encoders

Utilities (See Wiki/Utilites):

- PID controller
- FeedForward controller
- Trapezoidal motion profile controller
- Pure Pursuit
- Generic auto program builder
- Auto program UI selector
- Mathematical classes (Vector2D, Moving Average)

# Chapter 2

# Hierarchical Index

## 2.1 Class Hierarchy

This inheritance list is sorted roughly, but not completely, alphabetically:

# Chapter 3

# Class Index

## 3.1 Class List

Here are the classes, structs, unions and interfaces with brief descriptions:

# Chapter 4

# File Index

## 4.1 File List

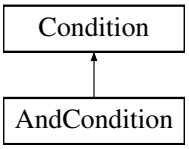
Here is a list of all documented files with brief descriptions:

# Chapter 5

# Class Documentation

## 5.1 AndCondition Class Reference

Inheritance diagram for AndCondition:




#### Public Member Functions

- **AndCondition** (Condition ∗A, Condition ∗B)
- bool test () override

### Public Member Functions inherited from Condition

- Condition ∗ **Or** (Condition ∗b)
- Condition ∗ **And** (Condition ∗b)

### 5.1.1 Member Function Documentation

#### 5.1.1.1 test()

```
bool AndCondition::test ( )  [inline], [override], [virtual]
```

Implements Condition.

The documentation for this class was generated from the following file:

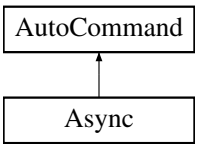
- src/utils/command_structure/auto_command.cpp

## 5.2 Async Class Reference

Async runs a command asynchronously will simply let it go and never look back THIS HAS A VERY NICHE USE CASE. THINK ABOUT IF YOU REALLY NEED IT.

`#include <auto_command.h>`

Inheritance diagram for Async:




#### Public Member Functions

- **Async** (AutoCommand ∗cmd)
- bool run () override

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand ∗ **withTimeout** (double t_seconds)
- AutoCommand ∗ **withCancelCondition** (Condition ∗true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition ∗ **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.2.1 Detailed Description

Async runs a command asynchronously will simply let it go and never look back THIS HAS A VERY NICHE USE CASE. THINK ABOUT IF YOU REALLY NEED IT.

### 5.2.2 Member Function Documentation

#### 5.2.2.1 run()

```
bool Async::run ( )  [override], [virtual]
```

Executes the command Overridden by child classes

**Returns**

true when the command is finished, false otherwise

Reimplemented from AutoCommand.

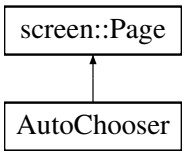
The documentation for this class was generated from the following files:

- include/utils/command_structure/auto_command.h
- src/utils/command_structure/auto_command.cpp

## 5.3 AutoChooser Class Reference

```
#include <auto_chooser.h>
```

Inheritance diagram for AutoChooser:




**Classes**

- struct entry_t

**Public Member Functions**

- AutoChooser (std::vector< std::string > paths, size_t def=0)
- void update (bool was_pressed, int x, int y)

  *collect data, respond to screen input, do fast things (runs at 50hz even if you're not focused on this Page (only drawn page gets touch updates))*
- void draw (vex::brain::lcd &, bool first_draw, unsigned int frame_number)

  *draw stored data to the screen (runs at 10 hz and only runs if this page is in front)*
- size_t get_choice ()

**Protected Attributes**

- size_t choice
- std::vector< entry_t > list

**Static Protected Attributes**

- static const size_t **width** = 380
- static const size_t **height** = 220

### 5.3.1 Detailed Description

Autochooser is a utility to make selecting robot autonomous programs easier source: RIT VexU Wiki During a season, we usually code between 4 and 6 autonomous programs. Most teams will change their entire robot program as a way of choosing autonomi but this may cause issues if you have an emergency patch to upload during a competition. This class was built as a way of using the robot screen to list autonomous programs, and the touchscreen to select them.

### 5.3.2 Constructor & Destructor Documentation

#### 5.3.2.1 AutoChooser()

```
AutoChooser::AutoChooser (
            std::vector< std::string > paths,
            size_t def = 0 )
```

Initialize the auto-chooser. This class places a choice menu on the brain screen, so the driver can choose which autonomous to run.

**Parameters**

| | |
|---|---|
| *brain* | the brain on which to draw the selection boxes |

### 5.3.3 Member Function Documentation

#### 5.3.3.1 draw()

```
void AutoChooser::draw (
            vex::brain::lcd & screen,
            bool first_draw,
            unsigned int frame_number )  [virtual]
```

draw stored data to the screen (runs at 10 hz and only runs if this page is in front)

**Parameters**

| | |
|---|---|
| *first_draw* | true if we just switched to this page |
| *frame_number* | frame of drawing we are on (basically an animation tick) |

Reimplemented from screen::Page.

#### 5.3.3.2 get_choice()

```
size_t AutoChooser::get_choice ( )
```

Get the currently selected auto choice

**Returns**

the identifier to the auto path

Return the selected autonomous

#### 5.3.3.3 update()

```
void AutoChooser::update (
            bool was_pressed,
            int x,
            int y )  [virtual]
```

collect data, respond to screen input, do fast things (runs at 50hz even if you're not focused on this Page (only drawn page gets touch updates))

**Parameters**

| | |
|---|---|
| *was_pressed* | true if the screen has been pressed |
| *x* | x position of screen press (if the screen was pressed) |
| *y* | y position of screen press (if the screen was pressed) |

Reimplemented from screen::Page.

### 5.3.4 Member Data Documentation

#### 5.3.4.1 choice

```
size_t AutoChooser::choice  [protected]
```

the current choice of auto

#### 5.3.4.2 list

```
std::vector<entry_t> AutoChooser::list  [protected]
```

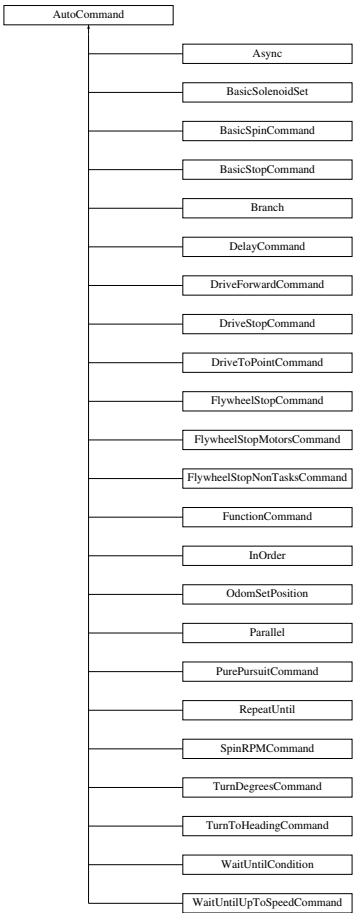
< a list of all possible auto choices

The documentation for this class was generated from the following files:

- include/utils/auto_chooser.h
- src/utils/auto_chooser.cpp

## 5.4 AutoCommand Class Reference

Inheritance diagram for AutoCommand:




### Public Member Functions

- virtual bool run ()
- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Public Attributes

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes

- static constexpr double **default_timeout** = 10.0

### 5.4.1 Member Function Documentation

#### 5.4.1.1 on_timeout()

```
virtual void AutoCommand::on_timeout ( )  [inline], [virtual]
```

What to do if we timeout instead of finishing. timeout is specified by the timeout seconds in the constructor

Reimplemented in InOrder, Parallel, Branch, RepeatUntil, DriveForwardCommand, TurnDegreesCommand, TurnToHeadingCommand, PurePursuitCommand, and DriveStopCommand.

#### 5.4.1.2 run()

```
virtual bool AutoCommand::run ( )  [inline], [virtual]
```

Executes the command Overridden by child classes

**Returns**

true when the command is finished, false otherwise

Reimplemented in FunctionCommand, WaitUntilCondition, InOrder, Parallel, Branch, Async, RepeatUntil, BasicSpinCommand, BasicStopCommand, BasicSolenoidSet, DelayCommand, DriveForwardCommand, TurnDegreesCommand, DriveToPointCommand, TurnToHeadingCommand, PurePursuitCommand, DriveStopCommand, OdomSetPosition, SpinRPMCommand, WaitUntilUpToSpeedCommand, FlywheelStopCommand, and FlywheelStopMotorsCommand.

### 5.4.2 Member Data Documentation

#### 5.4.2.1 timeout_seconds

```
double AutoCommand::timeout_seconds = default_timeout
```

How long to run until we cancel this command. If the command is cancelled, on_timeout() is called to allow any cleanup from the function. If the timeout_seconds <= 0, no timeout will be applied and this command will run forever A timeout can come in handy for some commands that can not reach the end due to some physical limitation such as

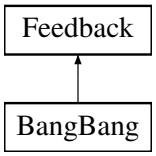
- a drive command hitting a wall and not being able to reach its target
- a command that waits until something is up to speed that never gets up to speed because of battery voltage
- something else...

The documentation for this class was generated from the following file:

- include/utils/command_structure/auto_command.h

## 5.5 BangBang Class Reference

Inheritance diagram for BangBang:




### Public Member Functions

- **BangBang** (double thresshold, double low, double high)
- void init (double start_pt, double set_pt, double start_vel=0.0, double end_vel=0.0) override
- double update (double val) override
- double get () override
- void set_limits (double lower, double upper) override
- bool is_on_target () override

### 5.5.1 Member Function Documentation

#### 5.5.1.1 get()

```
double BangBang::get ( )  [override], [virtual]
```

**Returns**

the last saved result from the feedback controller

Implements Feedback.

#### 5.5.1.2 init()

```
void BangBang::init (
            double start_pt,
            double set_pt,
            double start_vel = 0.0,
            double end_vel = 0.0 )  [override], [virtual]
```

Initialize the feedback controller for a movement

**Parameters**

| | |
|---|---|
| *start_pt* | the current sensor value |
| *set_pt* | where the sensor value should be |
| *start_vel* | Movement starting velocity |
| *end_vel* | Movement ending velocity |

Implements Feedback.

#### 5.5.1.3 is_on_target()

```
bool BangBang::is_on_target ( )  [override], [virtual]
```

**Returns**

true if the feedback controller has reached it's setpoint

Implements Feedback.

#### 5.5.1.4 set_limits()

```
void BangBang::set_limits (
            double lower,
            double upper )  [override], [virtual]
```

Clamp the upper and lower limits of the output. If both are 0, no limits should be applied.

**Parameters**

| | |
|---|---|
| *lower* | Upper limit |
| *upper* | Lower limit |

Implements Feedback.

#### 5.5.1.5 update()

```
double BangBang::update (
            double val )  [override], [virtual]
```

Iterate the feedback loop once with an updated sensor value

**Parameters**

| | |
|---|---|
| *val* | value from the sensor |

**Returns**

feedback loop result

Implements Feedback.

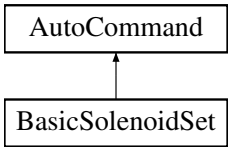
The documentation for this class was generated from the following files:

- include/utils/controls/bang_bang.h
- src/utils/controls/bang_bang.cpp

## 5.6 BasicSolenoidSet Class Reference

`#include <basic_command.h>`

Inheritance diagram for BasicSolenoidSet:




#### Public Member Functions

- BasicSolenoidSet (vex::pneumatics &solenoid, bool setting)

  *Construct a new BasicSolenoidSet Command.*
- bool run () override

  *Runs the BasicSolenoidSet Overrides run command from AutoCommand.*

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.6.1 Detailed Description

AutoCommand wrapper class for BasicSolenoidSet Using the Vex hardware functions

### 5.6.2 Constructor & Destructor Documentation

#### 5.6.2.1 BasicSolenoidSet()

```
BasicSolenoidSet::BasicSolenoidSet (
            vex::pneumatics & solenoid,
            bool setting )
```

Construct a new BasicSolenoidSet Command.

**Parameters**

| | |
|---|---|
| *solenoid* | Solenoid being set |
| *setting* | Setting of the solenoid in boolean (true,false) |

### 5.6.3 Member Function Documentation

#### 5.6.3.1 run()

```
bool BasicSolenoidSet::run ( )  [override], [virtual]
```

Runs the BasicSolenoidSet Overrides run command from AutoCommand.

**Returns**

True Command runs once

Reimplemented from AutoCommand.

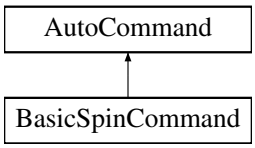
The documentation for this class was generated from the following files:

- include/utils/command_structure/basic_command.h
- src/utils/command_structure/basic_command.cpp

## 5.7 BasicSpinCommand Class Reference

```
#include <basic_command.h>
```

Inheritance diagram for BasicSpinCommand:




**Public Types**

- enum **type** { **percent** , **voltage** , **veocity** }

**Public Member Functions**

- BasicSpinCommand (vex::motor &motor, vex::directionType dir, BasicSpinCommand::type setting, double power)

  *Construct a new BasicSpinCommand.*
- bool run () override

  *Runs the BasicSpinCommand Overrides run from Auto Command.*

## Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

## Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

## Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.7.1 Detailed Description

AutoCommand wrapper class for BasicSpinCommand using the vex hardware functions

### 5.7.2 Constructor & Destructor Documentation

#### 5.7.2.1 BasicSpinCommand()

```
BasicSpinCommand::BasicSpinCommand (
            vex::motor & motor,
            vex::directionType dir,
            BasicSpinCommand::type setting,
            double power )
```

Construct a new BasicSpinCommand.

a BasicMotorSpin Command

**Parameters**

| | |
|---|---|
| *motor* | Motor to spin |
| *direc* | Direction of motor spin |
| *setting* | Power setting in volts,percentage,velocity |
| *power* | Value of desired power |
| *motor* | Motor port to spin |
| *dir* | Direction for spining |
| *setting* | Power setting in volts,percentage,velocity |
| *power* | Value of desired power |

### 5.7.3 Member Function Documentation

#### 5.7.3.1 run()

```
bool BasicSpinCommand::run ( )  [override], [virtual]
```

Runs the BasicSpinCommand Overrides run from Auto Command.

Run the BasicSpinCommand Overrides run from Auto Command.

**Returns**

True Async running command

True Command runs once

Reimplemented from AutoCommand.

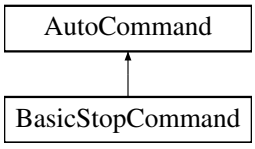
The documentation for this class was generated from the following files:

- include/utils/command_structure/basic_command.h
- src/utils/command_structure/basic_command.cpp

## 5.8 BasicStopCommand Class Reference

```
#include <basic_command.h>
```

Inheritance diagram for BasicStopCommand:




**Public Member Functions**

- BasicStopCommand (vex::motor &motor, vex::brakeType setting)

  *Construct a new BasicMotorStop Command.*
- bool run () override

  *Runs the BasicMotorStop Command Overrides run command from AutoCommand.*

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

**Additional Inherited Members**

## Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

## Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.8.1 Detailed Description

AutoCommand wrapper class for BasicStopCommand Using the Vex hardware functions

### 5.8.2 Constructor & Destructor Documentation

#### 5.8.2.1 BasicStopCommand()

```
BasicStopCommand::BasicStopCommand (
            vex::motor & motor,
            vex::brakeType setting )
```

Construct a new BasicMotorStop Command.

Construct a BasicMotorStop Command.

**Parameters**

| | |
|---|---|
| *motor* | The motor to stop |
| *setting* | The brake setting for the motor |
| *motor* | Motor to stop |
| *setting* | Braketype setting brake,coast,hold |

### 5.8.3 Member Function Documentation

#### 5.8.3.1 run()

```
bool BasicStopCommand::run ( )  [override], [virtual]
```

Runs the BasicMotorStop Command Overrides run command from AutoCommand.

Runs the BasicMotorStop command Ovverides run command from AutoCommand.

**Returns**

True Command runs once

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

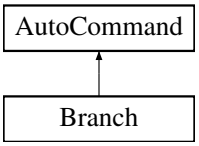
- include/utils/command_structure/basic_command.h
- src/utils/command_structure/basic_command.cpp

## 5.9 Branch Class Reference

Branch chooses from multiple options at runtime. the function decider returns an index into the choices vector If you wish to make no choice and skip this section, return NO_CHOICE; any choice that is out of bounds set to NO_CHOICE.

`#include <auto_command.h>`

Inheritance diagram for Branch:




### Public Member Functions

- **Branch** (Condition *cond, AutoCommand *false_choice, AutoCommand *true_choice)
- bool run () override
- void on_timeout () override

### Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.9.1 Detailed Description

Branch chooses from multiple options at runtime. the function decider returns an index into the choices vector If you wish to make no choice and skip this section, return NO_CHOICE; any choice that is out of bounds set to NO_CHOICE.

### 5.9.2 Member Function Documentation

#### 5.9.2.1 on_timeout()

```
void Branch::on_timeout ( )  [override], [virtual]
```

What to do if we timeout instead of finishing. timeout is specified by the timeout seconds in the constructor

Reimplemented from AutoCommand.

#### 5.9.2.2 run()

```
bool Branch::run ( )  [override], [virtual]
```

Executes the command Overridden by child classes

**Returns**

true when the command is finished, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/auto_command.h
- src/utils/command_structure/auto_command.cpp

## 5.10 screen::ButtonWidget Class Reference

Widget that does something when you tap it. The function is only called once when you first tap it.

```
#include <screen.h>
```

**Public Member Functions**

- ButtonWidget (std::function< void(void)> onpress, Rect rect, std::string name)
  *Create a Button widget.*
- ButtonWidget (void(*onpress)(), Rect rect, std::string name)
  *Create a Button widget.*
- bool update (bool was_pressed, int x, int y)
  *responds to user input*
- void **draw** (vex::brain::lcd &, bool first_draw, unsigned int frame_number)
  *draws the button to the screen*

### 5.10.1 Detailed Description

Widget that does something when you tap it. The function is only called once when you first tap it.

### 5.10.2 Constructor & Destructor Documentation

#### 5.10.2.1 ButtonWidget() [1/2]

```
screen::ButtonWidget::ButtonWidget (
            std::function< void(void)> onpress,
            Rect rect,
            std::string name )  [inline]
```

Create a Button widget.

**Parameters**

| | |
|---|---|
| *onpress* | the function to be called when the button is tapped |
| *rect* | the area the button should take up on the screen |
| *name* | the label put on the button |

#### 5.10.2.2 ButtonWidget() [2/2]

```
screen::ButtonWidget::ButtonWidget (
            void(*)() onpress,
            Rect rect,
            std::string name )  [inline]
```

Create a Button widget.

**Parameters**

| | |
|---|---|
| *onpress* | the function to be called when the button is tapped |
| *rect* | the area the button should take up on the screen |
| *name* | the label put on the button |

### 5.10.3 Member Function Documentation

#### 5.10.3.1 update()

```
bool screen::ButtonWidget::update (
            bool was_pressed,
            int x,
            int y )
```

responds to user input

**Parameters**

| | |
|---|---|
| *was_pressed* | if the screen is pressed |
| *x* | x position if the screen was pressed |
| *y* | y position if the screen was pressed |

**Returns**

true if the button was pressed

The documentation for this class was generated from the following files:

- include/subsystems/screen.h
- src/subsystems/screen.cpp

## 5.11 CommandController Class Reference

`#include <command_controller.h>`

### Public Member Functions

- **CommandController** ()

  *Create an empty CommandController. Add Command with CommandController::add()*
- CommandController (std::initializer_list< AutoCommand * > cmds)

  *Create a CommandController with commands pre added. More can be added with CommandController::add()*
- void add (std::vector< AutoCommand * > cmds)
- void add (AutoCommand *cmd, double timeout_seconds=10.0)
- void add (std::vector< AutoCommand * > cmds, double timeout_sec)
- void add_delay (int ms)
- void add_cancel_func (std::function< bool(void)> true_if_cancel)

  *add_cancel_func specifies that when this func evaluates to true, to cancel the command controller*
- void run ()
- bool last_command_timed_out ()

### 5.11.1 Detailed Description

File: command_controller.h Desc: A CommandController manages the AutoCommands that make up an autonomous route. The AutoCommands are kept in a queue and get executed and removed from the queue in FIFO order.

### 5.11.2 Constructor & Destructor Documentation

#### 5.11.2.1 CommandController()

```
CommandController::CommandController (
            std::initializer_list< AutoCommand * > cmds )  [inline]
```

Create a CommandController with commands pre added. More can be added with CommandController::add()

**Parameters**

| | |
|---|---|
| *cmds* | |

### 5.11.3 Member Function Documentation

#### 5.11.3.1 add() [1/3]

```
void CommandController::add (
            AutoCommand * cmd,
            double timeout_seconds = 10.0 )
```

File: command_controller.cpp Desc: A CommandController manages the AutoCommands that make up an autonomous route. The AutoCommands are kept in a queue and get executed and removed from the queue in FIFO order. Adds a command to the queue

**Parameters**

| | |
|---|---|
| *cmd* | the AutoCommand we want to add to our list |
| *timeout_seconds* | the number of seconds we will let the command run for. If it exceeds this, we cancel it and run on_timeout |

#### 5.11.3.2 add() [2/3]

```
void CommandController::add (
            std::vector< AutoCommand * > cmds )
```

Adds a command to the queue

**Parameters**

| | |
|---|---|
| *cmd* | the AutoCommand we want to add to our list |
| *timeout_seconds* | the number of seconds we will let the command run for. If it exceeds this, we cancel it and run on_timeout. if it is <= 0 no time out will be applied |

Add multiple commands to the queue. No timeout here.

**Parameters**

| | |
|---|---|
| *cmds* | the AutoCommands we want to add to our list |

#### 5.11.3.3 add() [3/3]

```
void CommandController::add (
            std::vector< AutoCommand * > cmds,
            double timeout_sec )
```

Add multiple commands to the queue. No timeout here.

**Parameters**

| | |
|---|---|
| *cmds* | the AutoCommands we want to add to our list Add multiple commands to the queue. No timeout here. |
| *cmds* | the AutoCommands we want to add to our list |
| *timeout_sec* | timeout in seconds to apply to all commands if they are still the default |

Add multiple commands to the queue. No timeout here.

**Parameters**

| | |
|---|---|
| *cmds* | the AutoCommands we want to add to our list |
| *timeout* | timeout in seconds to apply to all commands if they are still the default |

#### 5.11.3.4 add_cancel_func()

```
void CommandController::add_cancel_func (
            std::function< bool(void)> true_if_cancel )
```

add_cancel_func specifies that when this func evaluates to true, to cancel the command controller

**Parameters**

| | |
|---|---|
| *true_if_cancel* | a function that returns true when we want to cancel the command controller |

#### 5.11.3.5 add_delay()

```
void CommandController::add_delay (
            int ms )
```

Adds a command that will delay progression of the queue

**Parameters**

| | |
|---|---|
| *ms* | - number of milliseconds to wait before continuing execution of autonomous |

#### 5.11.3.6 last_command_timed_out()

```
bool CommandController::last_command_timed_out ( )
```

last_command_timed_out tells how the last command ended Use this if you want to make decisions based on the end of the last command

**Returns**

true if the last command timed out. false if it finished regularly

#### 5.11.3.7 run()

```
void CommandController::run ( )
```

Begin execution of the queue Execute and remove commands in FIFO order

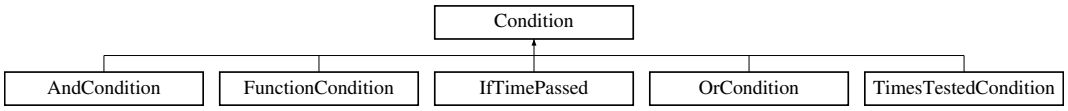
The documentation for this class was generated from the following files:

- include/utils/command_structure/command_controller.h
- src/utils/command_structure/command_controller.cpp

## 5.12 Condition Class Reference

```
#include <auto_command.h>
```

Inheritance diagram for Condition:




**Public Member Functions**

- Condition ∗ **Or** (Condition ∗b)
- Condition ∗ **And** (Condition ∗b)
- virtual bool **test** ()=0

### 5.12.1 Detailed Description

File: auto_command.h Desc: Interface for module-specifc commands A Condition is a function that returns true or false is_even is a predicate that would return true if a number is even For our purposes, a Condition is a choice to be made at runtime drive_sys.reached_point(10, 30) is a predicate time.has_elapsed(10, vex::seconds) is a predicate extend this class for different choices you wish to make

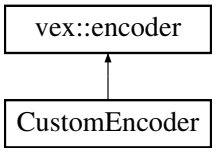
The documentation for this class was generated from the following files:

- include/utils/command_structure/auto_command.h
- src/utils/command_structure/auto_command.cpp

## 5.13 CustomEncoder Class Reference

```
#include <custom_encoder.h>
```

Inheritance diagram for CustomEncoder:



**Public Member Functions**

- CustomEncoder (vex::triport::port &port, double ticks_per_rev)
- void setRotation (double val, vex::rotationUnits units)
- void setPosition (double val, vex::rotationUnits units)
- double rotation (vex::rotationUnits units)
- double position (vex::rotationUnits units)
- double velocity (vex::velocityUnits units)

## 5.13.1 Detailed Description

A wrapper class for the vex encoder that allows the use of 3rd party encoders with different tick-per-revolution values.

## 5.13.2 Constructor & Destructor Documentation

### 5.13.2.1 CustomEncoder()

```
CustomEncoder::CustomEncoder (
            vex::triport::port & port,
            double ticks_per_rev )
```

Construct an encoder with a custom number of ticks

**Parameters**

| | |
|---|---|
| *port* | the triport port on the brain the encoder is plugged into |
| *ticks_per_rev* | the number of ticks the encoder will report for one revolution |

## 5.13.3 Member Function Documentation

### 5.13.3.1 position()

```
double CustomEncoder::position (
            vex::rotationUnits units )
```

get the position that the encoder is at

**Parameters**

| | |
|---|---|
| *units* | the unit we want the return value to be in |

**Returns**

the position of the encoder in the units specified

#### 5.13.3.2 rotation()

```
double CustomEncoder::rotation (
            vex::rotationUnits units )
```

get the rotation that the encoder is at

**Parameters**

| | |
|---|---|
| *units* | the unit we want the return value to be in |

**Returns**

the rotation of the encoder in the units specified

#### 5.13.3.3 setPosition()

```
void CustomEncoder::setPosition (
            double val,
            vex::rotationUnits units )
```

sets the stored position of the encoder. Any further movements will be from this value

**Parameters**

| | |
|---|---|
| *val* | the numerical value of the position we are setting to |
| *units* | the unit of val |

#### 5.13.3.4 setRotation()

```
void CustomEncoder::setRotation (
            double val,
            vex::rotationUnits units )
```

sets the stored rotation of the encoder. Any further movements will be from this value

**Parameters**

| | |
|---|---|
| *val* | the numerical value of the angle we are setting to |
| *units* | the unit of val |

#### 5.13.3.5 velocity()

```
double CustomEncoder::velocity (
            vex::velocityUnits units )
```

get the velocity that the encoder is moving at

**Parameters**

| | |
|---|---|
| *units* | the unit we want the return value to be in |

**Returns**

the velocity of the encoder in the units specified

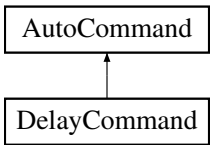
The documentation for this class was generated from the following files:

- include/subsystems/custom_encoder.h
- src/subsystems/custom_encoder.cpp

## 5.14 DelayCommand Class Reference

`#include <delay_command.h>`

Inheritance diagram for DelayCommand:




### Public Member Functions

- DelayCommand (int ms)
- bool run () override

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.14.1 Detailed Description

File: delay_command.h Desc: A DelayCommand will make the robot wait the set amount of milliseconds before continuing execution of the autonomous route

### 5.14.2 Constructor & Destructor Documentation

#### 5.14.2.1 DelayCommand()

```
DelayCommand::DelayCommand (
            int ms )  [inline]
```

Construct a delay command

**Parameters**

| | |
|---|---|
| *ms* | the number of milliseconds to delay for |

### 5.14.3 Member Function Documentation

#### 5.14.3.1 run()

```
bool DelayCommand::run ( )  [inline], [override], [virtual]
```

Delays for the amount of milliseconds stored in the command Overrides run from AutoCommand

**Returns**

true when complete

Reimplemented from AutoCommand.

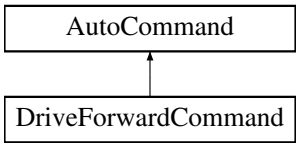
The documentation for this class was generated from the following file:

- include/utils/command_structure/delay_command.h

## 5.15 DriveForwardCommand Class Reference

```
#include <drive_commands.h>
```

Inheritance diagram for DriveForwardCommand:



#### Public Member Functions

- DriveForwardCommand (TankDrive &drive_sys, Feedback &feedback, double inches, directionType dir, double max_speed=1, double end_speed=0)
- bool run () override
- void on_timeout () override

### Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.15.1 Detailed Description

AutoCommand wrapper class for the drive_forward function in the TankDrive class

## 5.15.2 Constructor & Destructor Documentation

### 5.15.2.1 DriveForwardCommand()

```
DriveForwardCommand::DriveForwardCommand (
            TankDrive & drive_sys,
            Feedback & feedback,
            double inches,
            directionType dir,
            double max_speed = 1,
            double end_speed = 0 )
```

File: drive_commands.h Desc: Holds all the AutoCommand subclasses that wrap (currently) TankDrive functions

Currently includes:

- drive_forward
- turn_degrees
- drive_to_point
- turn_to_heading
- stop

Also holds AutoCommand subclasses that wrap OdometryBase functions

Currently includes:

- set_position Construct a DriveForward Command

**Parameters**

| | |
|---|---|
| *drive_sys* | the drive system we are commanding |
| *feedback* | the feedback controller we are using to execute the drive |
| *inches* | how far forward to drive |
| *dir* | the direction to drive |
| *max_speed* | 0 -> 1 percentage of the drive systems speed to drive at |

### 5.15.3 Member Function Documentation

#### 5.15.3.1 on_timeout()

```
void DriveForwardCommand::on_timeout ( )  [override], [virtual]
```

Cleans up drive system if we time out before finishing

reset the drive system if we timeout

Reimplemented from AutoCommand.

#### 5.15.3.2 run()

```
bool DriveForwardCommand::run ( )  [override], [virtual]
```

Run drive_forward Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

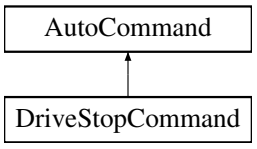
The documentation for this class was generated from the following files:

- include/utils/command_structure/drive_commands.h
- src/utils/command_structure/drive_commands.cpp

## 5.16 DriveStopCommand Class Reference

```
#include <drive_commands.h>
```

Inheritance diagram for DriveStopCommand:



#### Public Member Functions

- DriveStopCommand (TankDrive &drive_sys)
- bool run () override
- void on_timeout () override

### Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.16.1 Detailed Description

AutoCommand wrapper class for the stop() function in the TankDrive class

## 5.16.2 Constructor & Destructor Documentation

### 5.16.2.1 DriveStopCommand()

```
DriveStopCommand::DriveStopCommand (
            TankDrive & drive_sys )
```

Construct a DriveStop Command

**Parameters**

| | |
|---|---|
| *drive_sys* | the drive system we are commanding |

## 5.16.3 Member Function Documentation

### 5.16.3.1 on_timeout()

```
void DriveStopCommand::on_timeout ( )  [override], [virtual]
```

What to do if we timeout instead of finishing. timeout is specified by the timeout seconds in the constructor

Reimplemented from AutoCommand.

#### 5.16.3.2 run()

```
bool DriveStopCommand::run ( )  [override], [virtual]
```

Stop the drive system Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Stop the drive train Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

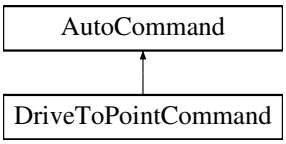
The documentation for this class was generated from the following files:

- include/utils/command_structure/drive_commands.h
- src/utils/command_structure/drive_commands.cpp

## 5.17 DriveToPointCommand Class Reference

```
#include <drive_commands.h>
```

Inheritance diagram for DriveToPointCommand:




### Public Member Functions

- DriveToPointCommand (TankDrive &drive_sys, Feedback &feedback, double x, double y, directionType dir, double max_speed=1, double end_speed=0)
- DriveToPointCommand (TankDrive &drive_sys, Feedback &feedback, point_t point, directionType dir, double max_speed=1, double end_speed=0)
- bool run () override

## Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Additional Inherited Members

## Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

## Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.17.1 Detailed Description

AutoCommand wrapper class for the drive_to_point function in the TankDrive class

## 5.17.2 Constructor & Destructor Documentation

### 5.17.2.1 DriveToPointCommand() [1/2]

```
DriveToPointCommand::DriveToPointCommand (
            TankDrive & drive_sys,
            Feedback & feedback,
            double x,
            double y,
            directionType dir,
            double max_speed = 1,
            double end_speed = 0 )
```

Construct a DriveForward Command

**Parameters**

| | |
|---|---|
| *drive_sys* | the drive system we are commanding |
| *feedback* | the feedback controller we are using to execute the drive |
| *x* | where to drive in the x dimension |
| *y* | where to drive in the y dimension |
| *dir* | the direction to drive |
| *max_speed* | 0 -> 1 percentage of the drive systems speed to drive at |

### 5.17.2.2 DriveToPointCommand() [2/2]

```
DriveToPointCommand::DriveToPointCommand (
```

```
TankDrive & drive_sys,
Feedback & feedback,
point_t point,
directionType dir,
double max_speed = 1,
double end_speed = 0 )
```

Construct a DriveForward Command

**Parameters**

| | |
|---|---|
| *drive_sys* | the drive system we are commanding |
| *feedback* | the feedback controller we are using to execute the drive |
| *point* | the point to drive to |
| *dir* | the direction to drive |
| *max_speed* | 0 -> 1 percentage of the drive systems speed to drive at |

### 5.17.3 Member Function Documentation

#### 5.17.3.1 run()

```
bool DriveToPointCommand::run ( )  [override], [virtual]
```

Run drive_to_point Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/drive_commands.h
- src/utils/command_structure/drive_commands.cpp

## 5.18 AutoChooser::entry_t Struct Reference

```
#include <auto_chooser.h>
```

**Public Attributes**

- Rect **rect**
- std::string name

### 5.18.1 Detailed Description

entry_t is a datatype used to store information that the chooser knows about an auto selection button

### 5.18.2 Member Data Documentation

#### 5.18.2.1 name

```
std::string AutoChooser::entry_t::name
```

name of the auto repretsented by the block

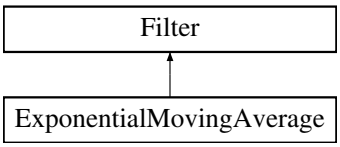
The documentation for this struct was generated from the following file:

- include/utils/auto_chooser.h

## 5.19 ExponentialMovingAverage Class Reference

```
#include <moving_average.h>
```

Inheritance diagram for ExponentialMovingAverage:




#### Public Member Functions

- ExponentialMovingAverage (int buffer_size)
- ExponentialMovingAverage (int buffer_size, double starting_value)
- void add_entry (double n)
- double get_value ()
- int get_size ()

### Public Member Functions inherited from Filter

- virtual double get_value () const =0

### 5.19.1 Detailed Description

ExponentialMovingAverage

An exponential moving average is a way of smoothing out noisy data. For many sensor readings, the noise is roughly symmetric around the actual value. This means that if you collect enough samples those that are too high are cancelled out by the samples that are too low leaving the real value.

A simple mobing average lags significantly with time as it has to counteract old samples. An exponential moving average keeps more up to date by weighting newer readings higher than older readings so it is more up to date while also still smoothed.

The ExponentialMovingAverage class provides an simple interface to do this smoothing from our noisy sensor values.

### 5.19.2 Constructor & Destructor Documentation

#### 5.19.2.1 ExponentialMovingAverage() [1/2]

```
ExponentialMovingAverage::ExponentialMovingAverage (
            int buffer_size )
```

Create a moving average calculator with 0 as the default value

**Parameters**

| | |
|---|---|
| *buffer_size* | The size of the buffer. The number of samples that constitute a valid reading |

#### 5.19.2.2 ExponentialMovingAverage() [2/2]

```
ExponentialMovingAverage::ExponentialMovingAverage (
            int buffer_size,
            double starting_value )
```

Create a moving average calculator with a specified default value

**Parameters**

| | |
|---|---|
| *buffer_size* | The size of the buffer. The number of samples that constitute a valid reading |
| *starting_value* | The value that the average will be before any data is added |

### 5.19.3 Member Function Documentation

#### 5.19.3.1 add_entry()

```
void ExponentialMovingAverage::add_entry (
            double n )  [virtual]
```

Add a reading to the buffer Before: [ 1 1 2 2 3 3] => 2 ^ After: [ 2 1 2 2 3 3] => 2.16 ^

**Parameters**

| | |
|---|---|
| *n* | the sample that will be added to the moving average. |

Implements Filter.

#### 5.19.3.2 get_size()

```
int ExponentialMovingAverage::get_size ( )
```

How many samples the average is made from

**Returns**

the number of samples used to calculate this average

#### 5.19.3.3 get_value()

```
double ExponentialMovingAverage::get_value ( )
```

Returns the average based off of all the samples collected so far

**Returns**

the calculated average. sum(samples)/numsamples

How many samples the average is made from

**Returns**

the number of samples used to calculate this average

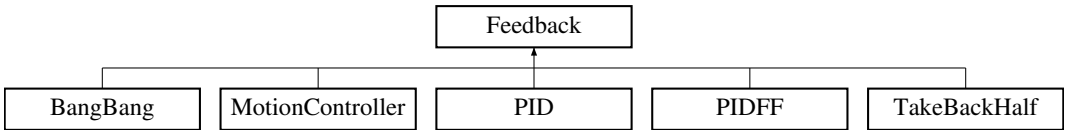
The documentation for this class was generated from the following files:

- include/utils/moving_average.h
- src/utils/moving_average.cpp

## 5.20 Feedback Class Reference

```
#include <feedback_base.h>
```

Inheritance diagram for Feedback:




### Public Member Functions

- virtual void init (double start_pt, double set_pt, double start_vel=0.0, double end_vel=0.0)=0
- virtual double update (double val)=0
- virtual double get ()=0
- virtual void set_limits (double lower, double upper)=0
- virtual bool is_on_target ()=0

### 5.20.1 Detailed Description

Interface so that subsystems can easily switch between feedback loops

**Author**

Ryan McGee

**Date**

9/25/2022

## 5.20.2 Member Function Documentation

### 5.20.2.1 get()

```
virtual double Feedback::get ( )  [pure virtual]
```

**Returns**

the last saved result from the feedback controller

Implemented in BangBang, MotionController, PID, PIDFF, and TakeBackHalf.

### 5.20.2.2 init()

```
virtual void Feedback::init (
            double start_pt,
            double set_pt,
            double start_vel = 0.0,
            double end_vel = 0.0 )  [pure virtual]
```

Initialize the feedback controller for a movement

**Parameters**

| | |
|---|---|
| *start_pt* | the current sensor value |
| *set_pt* | where the sensor value should be |
| *start_vel* | Movement starting velocity |
| *end_vel* | Movement ending velocity |

Implemented in MotionController, PIDFF, PID, BangBang, and TakeBackHalf.

### 5.20.2.3 is_on_target()

```
virtual bool Feedback::is_on_target ( )  [pure virtual]
```

**Returns**

true if the feedback controller has reached it's setpoint

Implemented in BangBang, MotionController, PID, PIDFF, and TakeBackHalf.

### 5.20.2.4 set_limits()

```
virtual void Feedback::set_limits (
            double lower,
            double upper )  [pure virtual]
```

Clamp the upper and lower limits of the output. If both are 0, no limits should be applied.

**Parameters**

| | |
|---|---|
| *lower* | Upper limit |
| *upper* | Lower limit |

Implemented in BangBang, MotionController, PID, PIDFF, and TakeBackHalf.

#### 5.20.2.5 update()

```
virtual double Feedback::update (
            double val )  [pure virtual]
```

Iterate the feedback loop once with an updated sensor value

**Parameters**

| | |
|---|---|
| *val* | value from the sensor |

**Returns**

feedback loop result

Implemented in MotionController, PID, BangBang, PIDFF, and TakeBackHalf.

The documentation for this class was generated from the following file:

- include/utils/controls/feedback_base.h

## 5.21 FeedForward Class Reference

```
#include <feedforward.h>
```

### Classes

- struct ff_config_t

### Public Member Functions

- FeedForward (ff_config_t &cfg)
- double calculate (double v, double a, double pid_ref=0.0)

  *Perform the feedforward calculation.*

### 5.21.1 Detailed Description

FeedForward

Stores the feedfoward constants, and allows for quick computation. Feedfoward should be used in systems that require smooth precise movements and have high inertia, such as drivetrains and lifts.

This is best used alongside a PID loop, with the form: output = pid.get() + feedforward.calculate(v, a);

In this case, the feedforward does the majority of the heavy lifting, and the pid loop only corrects for inconsistencies

For information about tuning feedforward, I reccommend looking at this post: https://www.chiefdelphi.com/t/paper-frc-drivetrain-characterization/160915 (yes I know it's for FRC but trust me, it's useful)

**Author**

Ryan McGee

**Date**

6/13/2022

### 5.21.2 Constructor & Destructor Documentation

#### 5.21.2.1 FeedForward()

```
FeedForward::FeedForward (
            ff_config_t & cfg )  [inline]
```

Creates a FeedForward object.

**Parameters**

| | |
|---|---|
| *cfg* | Configuration Struct for tuning |

### 5.21.3 Member Function Documentation

#### 5.21.3.1 calculate()

```
double FeedForward::calculate (
            double v,
            double a,
            double pid_ref = 0.0 )  [inline]
```

Perform the feedforward calculation.

This calculation is the equation: F = kG + kS∗sgn(v) + kV∗v + kA∗a

**Parameters**

| | |
|---|---|
| *v* | Requested velocity of system |
| *a* | Requested acceleration of system |

**Returns**

A feedforward that should closely represent the system if tuned correctly

The documentation for this class was generated from the following file:

- include/utils/controls/feedforward.h

## 5.22 FeedForward::ff_config_t Struct Reference

`#include <feedforward.h>`

### Public Attributes

- double kS
- double kV
- double kA
- double kG

### 5.22.1 Detailed Description

ff_config_t holds the parameters to make the theoretical model of a real world system equation is of the form kS if the system is not stopped, 0 otherwise

- kV $*$ desired velocity
- kA $*$ desired acceleration
- kG

### 5.22.2 Member Data Documentation

#### 5.22.2.1 kA

`double FeedForward::ff_config_t::kA`

kA - Acceleration coefficient: the power required to change the mechanism's speed. Multiplied by the requested acceleration.

#### 5.22.2.2 kG

```
double FeedForward::ff_config_t::kG
```

kG - Gravity coefficient: only needed for lifts. The power required to overcome gravity and stay at steady state.

#### 5.22.2.3 kS

```
double FeedForward::ff_config_t::kS
```

Coefficient to overcome static friction: the point at which the motor *starts* to move.

#### 5.22.2.4 kV

```
double FeedForward::ff_config_t::kV
```

Veclocity coefficient: the power required to keep the mechanism in motion. Multiplied by the requested velocity.

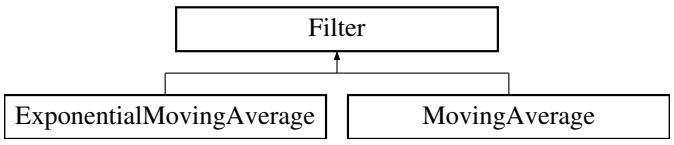
The documentation for this struct was generated from the following file:

- include/utils/controls/feedforward.h

## 5.23 Filter Class Reference

```
#include <moving_average.h>
```

Inheritance diagram for Filter:




### Public Member Functions

- virtual void add_entry (double n)=0
- virtual double get_value () const =0

### 5.23.1 Detailed Description

Interface for filters Use add_entry to supply data and get_value to retrieve the filtered value

### 5.23.2 Member Function Documentation

#### 5.23.2.1 add_entry()

```
virtual void Filter::add_entry (
            double n )  [pure virtual]
```

Implemented in MovingAverage, and ExponentialMovingAverage.

#### 5.23.2.2 get_value()

```
virtual double Filter::get_value ( ) const  [pure virtual]
```

Implemented in MovingAverage.

The documentation for this class was generated from the following file:

- include/utils/moving_average.h

## 5.24 Flywheel Class Reference

```
#include <flywheel.h>
```

#### Public Member Functions

- Flywheel (vex::motor_group &motors, Feedback &feedback, FeedForward &helper, const double ratio, Filter &filt)
- double get_target () const
- double getRPM () const
- vex::motor_group & get_motors () const
- void spin_manual (double speed, directionType dir=fwd)
- void spin_rpm (double rpm)
- void stop ()
- bool is_on_target ()

  *check if the feedback controller thinks the flywheel is on target*
- screen::Page * Page () const

  *Creates a page displaying info about the flywheel.*
- AutoCommand * SpinRpmCmd (int rpm)

  *Creates a new auto command to spin the flywheel at the desired velocity.*
- AutoCommand * WaitUntilUpToSpeedCmd ()

  *Creates a new auto command that will hold until the flywheel has its target as defined by its feedback controller.*

#### Friends

- class **FlywheelPage**
- int spinRPMTask (void *wheelPointer)

### 5.24.1 Detailed Description

a Flywheel class that handles all control of a high inertia spinning disk It gives multiple options for what control system to use in order to control wheel velocity and functions alerting the user when the flywheel is up to speed. Flywheel is a set and forget class. Once you create it you can call spin_rpm or stop on it at any time and it will take all necessary steps to accomplish this

### 5.24.2 Constructor & Destructor Documentation

#### 5.24.2.1 Flywheel()

```
Flywheel::Flywheel (
            vex::motor_group & motors,
            Feedback & feedback,
            FeedForward & helper,
            const double ratio,
            Filter & filt )
```

Create the Flywheel object using PID + feedforward for control.

**Parameters**

| | |
|---|---|
| *motors* | pointer to the motors on the fly wheel |
| *feedback* | a feedback controleller |
| *helper* | a feedforward config (only kV is used) to help the feedback controller along |
| *ratio* | ratio of the gears from the motor to the flywheel just multiplies the velocity |
| *filter* | the filter to use to smooth noisy motor readings |

### 5.24.3 Member Function Documentation

#### 5.24.3.1 get_motors()

```
motor_group & Flywheel::get_motors ( ) const
```

Returns the motors

**Returns**

the motors used to run the flywheel

#### 5.24.3.2 get_target()

```
double Flywheel::get_target ( ) const
```

Return the target_rpm that the flywheel is currently trying to achieve

**Returns**

target_rpm the target rpm

Return the current value that the target_rpm should be set to

#### 5.24.3.3 getRPM()

```
double Flywheel::getRPM ( ) const
```

return the velocity of the flywheel

#### 5.24.3.4 is_on_target()

```
bool Flywheel::is_on_target ( )  [inline]
```

check if the feedback controller thinks the flywheel is on target

**Returns**

true if on target

#### 5.24.3.5 Page()

```
screen::Page * Flywheel::Page ( ) const
```

Creates a page displaying info about the flywheel.

**Returns**

the page should be used for `screen::start_screen(screen, {fw.Page()});

#### 5.24.3.6 spin_manual()

```
void Flywheel::spin_manual (
            double speed,
            directionType dir = fwd )
```

Spin motors using voltage; defaults forward at 12 volts FOR USE BY OPCONTROL AND AUTONOMOUS - this only applies if the target_rpm thread is not running

**Parameters**

| | |
|---|---|
| *speed* | - speed (between -1 and 1) to set the motor |
| *dir* | - direction that the motor moves in; defaults to forward |

Spin motors using voltage; defaults forward at 12 volts FOR USE BY OPCONTROL AND AUTONOMOUS - this only applies if the RPM thread is not running

**Parameters**

| | |
|---|---|
| *speed* | - speed (between -1 and 1) to set the motor |
| *dir* | - direction that the motor moves in; defaults to forward |

#### 5.24.3.7 spin_rpm()

```
void Flywheel::spin_rpm (
            double input_rpm )
```

starts or sets the target_rpm thread at new value what control scheme is dependent on control_style

**Parameters**

| | |
|---|---|
| *rpm* | - the target_rpm we want to spin at |

starts or sets the RPM thread at new value what control scheme is dependent on control_style

**Parameters**

| | |
|---|---|
| *input_rpm* | - set the current RPM |

#### 5.24.3.8 SpinRpmCmd()

```
AutoCommand * Flywheel::SpinRpmCmd (
            int rpm )  [inline]
```

Creates a new auto command to spin the flywheel at the desired velocity.

**Parameters**

| | |
|---|---|
| *rpm* | the rpm to spin at |

**Returns**

an auto command to add to a command controller

#### 5.24.3.9 stop()

```
void Flywheel::stop ( )
```

Stops the motors. If manually spinning, this will do nothing just call spin_mainual(0.0) to send 0 volts

stop the RPM thread and the wheel

#### 5.24.3.10 WaitUntilUpToSpeedCmd()

```
AutoCommand * Flywheel::WaitUntilUpToSpeedCmd ( )  [inline]
```

Creates a new auto command that will hold until the flywheel has its target as defined by its feedback controller.

**Returns**

an auto command to add to a command controller

### 5.24.4 Friends And Related Symbol Documentation

#### 5.24.4.1 spinRPMTask

```
int spinRPMTask (
            void * wheelPointer )  [friend]
```

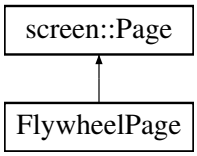
Runs a thread that keeps track of updating flywheel RPM and controlling it accordingly

The documentation for this class was generated from the following files:

- include/subsystems/flywheel.h
- src/subsystems/flywheel.cpp

## 5.25 FlywheelPage Class Reference

Inheritance diagram for FlywheelPage:




#### Public Member Functions

- **FlywheelPage** (const Flywheel &fw)
- void update (bool, int, int) override
- void draw (vex::brain::lcd &screen, bool, unsigned int) override

#### Static Public Attributes

- static const size_t **window_size** = 40

### 5.25.1 Member Function Documentation

#### 5.25.1.1 draw()

```
void FlywheelPage::draw (
            vex::brain::lcd & screen,
            bool ,
            unsigned int  )  [inline], [override], [virtual]
```

**See also**

Page::draw

Reimplemented from screen::Page.

#### 5.25.1.2 update()

```
void FlywheelPage::update (
            bool ,
            int ,
            int  )  [inline], [override], [virtual]
```

**See also**

Page::update

Reimplemented from screen::Page.

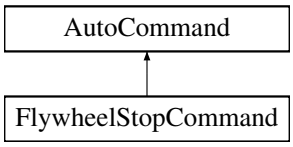
The documentation for this class was generated from the following file:

- src/subsystems/flywheel.cpp

## 5.26 FlywheelStopCommand Class Reference

```
#include <flywheel_commands.h>
```

Inheritance diagram for FlywheelStopCommand:




### Public Member Functions

- FlywheelStopCommand (Flywheel &flywheel)
- bool run () override

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.26.1 Detailed Description

AutoCommand wrapper class for the stop function in the Flywheel class

## 5.26.2 Constructor & Destructor Documentation

### 5.26.2.1 FlywheelStopCommand()

```
FlywheelStopCommand::FlywheelStopCommand (
            Flywheel & flywheel )
```

Construct a FlywheelStopCommand

**Parameters**

| | |
|---|---|
| *flywheel* | the flywheel system we are commanding |

## 5.26.3 Member Function Documentation

### 5.26.3.1 run()

```
bool FlywheelStopCommand::run ( )  [override], [virtual]
```

Run stop Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

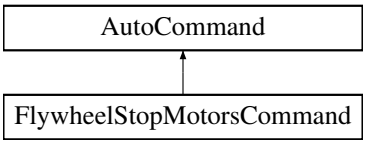
The documentation for this class was generated from the following files:

- include/utils/command_structure/flywheel_commands.h
- src/utils/command_structure/flywheel_commands.cpp

# 5.27 FlywheelStopMotorsCommand Class Reference

```
#include <flywheel_commands.h>
```

Inheritance diagram for FlywheelStopMotorsCommand:



#### Public Member Functions

- FlywheelStopMotorsCommand (Flywheel &flywheel)
- bool run () override

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.27.1 Detailed Description

AutoCommand wrapper class for the stopMotors function in the Flywheel class

## 5.27.2 Constructor & Destructor Documentation

### 5.27.2.1 FlywheelStopMotorsCommand()

```
FlywheelStopMotorsCommand::FlywheelStopMotorsCommand (
            Flywheel & flywheel )
```

Construct a FlywheeStopMotors Command

**Parameters**

| | |
|---|---|
| *flywheel* | the flywheel system we are commanding |

## 5.27.3 Member Function Documentation

### 5.27.3.1 run()

```
bool FlywheelStopMotorsCommand::run ( )  [override], [virtual]
```

Run stop Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

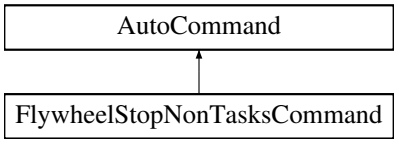
The documentation for this class was generated from the following files:

- include/utils/command_structure/flywheel_commands.h
- src/utils/command_structure/flywheel_commands.cpp

## 5.28 FlywheelStopNonTasksCommand Class Reference

`#include <flywheel_commands.h>`

Inheritance diagram for FlywheelStopNonTasksCommand:




**Additional Inherited Members**

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.28.1 Detailed Description

AutoCommand wrapper class for the stopNonTasks function in the Flywheel class

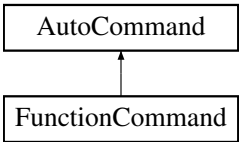
The documentation for this class was generated from the following files:

- include/utils/command_structure/flywheel_commands.h
- src/utils/command_structure/flywheel_commands.cpp

## 5.29 FunctionCommand Class Reference

`#include <auto_command.h>`

Inheritance diagram for FunctionCommand:




#### Public Member Functions

- **FunctionCommand** (std::function< bool(void)> f)
- bool run ()

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.29.1 Detailed Description

FunctionCommand is fun and good way to do simple things Printing, launching nukes, and other quick and dirty one time things

### 5.29.2 Member Function Documentation

#### 5.29.2.1 run()

```
bool FunctionCommand::run ( )  [inline], [virtual]
```

Executes the command Overridden by child classes

**Returns**

true when the command is finished, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following file:

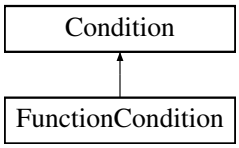
- include/utils/command_structure/auto_command.h

## 5.30 FunctionCondition Class Reference

FunctionCondition is a quick and dirty Condition to wrap some expression that should be evaluated at runtime.

```
#include <auto_command.h>
```

Inheritance diagram for FunctionCondition:




**Public Member Functions**

- **FunctionCondition** (std::function< bool()> cond, std::function< void(void)> timeout=[]() {})
- bool test () override

### Public Member Functions inherited from Condition

- Condition * **Or** (Condition *b)
- Condition * **And** (Condition *b)

### 5.30.1 Detailed Description

FunctionCondition is a quick and dirty Condition to wrap some expression that should be evaluated at runtime.

### 5.30.2 Member Function Documentation

#### 5.30.2.1 test()

```
bool FunctionCondition::test ( )  [override], [virtual]
```

Implements Condition.

The documentation for this class was generated from the following files:

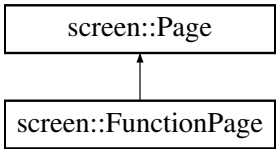
- include/utils/command_structure/auto_command.h
- src/utils/command_structure/auto_command.cpp

## 5.31 screen::FunctionPage Class Reference

Simple page that stores no internal data. the draw and update functions use only global data rather than storing anything.

```
#include <screen.h>
```

Inheritance diagram for screen::FunctionPage:




#### Public Member Functions

- FunctionPage (update_func_t update_f, draw_func_t draw_t)
  *Creates a function page.*
- void update (bool was_pressed, int x, int y) override
  *update uses the supplied update function to update this page*
- void draw (vex::brain::lcd &, bool first_draw, unsigned int frame_number) override
  *draw uses the supplied draw function to draw to the screen*

### 5.31.1 Detailed Description

Simple page that stores no internal data. the draw and update functions use only global data rather than storing anything.

### 5.31.2 Constructor & Destructor Documentation

#### 5.31.2.1 FunctionPage()

```
screen::FunctionPage::FunctionPage (
            update_func_t update_f,
            draw_func_t draw_f )
```

Creates a function page.

FunctionPage.

**Parameters**

| | |
|---|---|
| *update_f* | the function called every tick to respond to user input or do data collection |
| *draw_t* | the function called to draw to the screen |
| *update_f* | drawing function |
| *draw_f* | drawing function |

### 5.31.3 Member Function Documentation

#### 5.31.3.1 draw()

```
void screen::FunctionPage::draw (
            vex::brain::lcd & screen,
            bool first_draw,
            unsigned int frame_number )  [override], [virtual]
```

draw uses the supplied draw function to draw to the screen

**See also**

Page::draw

Reimplemented from screen::Page.

#### 5.31.3.2 update()

```
void screen::FunctionPage::update (
            bool was_pressed,
            int x,
            int y )  [override], [virtual]
```

update uses the supplied update function to update this page

**See also**

Page::update

Reimplemented from screen::Page.

The documentation for this class was generated from the following files:

- include/subsystems/screen.h
- src/subsystems/screen.cpp

## 5.32 GenericAuto Class Reference

```
#include <generic_auto.h>
```

**Public Member Functions**

- bool run (bool blocking)
- void add (state_ptr new_state)
- void add_async (state_ptr async_state)
- void add_delay (int ms)

## 5.32.1 Detailed Description

GenericAuto provides a pleasant interface for organizing an auto path steps of the path can be added with add() and when ready, calling run() will begin executing the path

## 5.32.2 Member Function Documentation

### 5.32.2.1 add()

```
void GenericAuto::add (
            state_ptr new_state )
```

Add a new state to the autonomous via function point of type "bool (ptr∗)()"

**Parameters**

| | |
|---|---|
| *new_state* | the function to run |

### 5.32.2.2 add_async()

```
void GenericAuto::add_async (
            state_ptr async_state )
```

Add a new state to the autonomous via function point of type "bool (ptr∗)()" that will run asynchronously

**Parameters**

| | |
|---|---|
| *async_state* | the function to run |

### 5.32.2.3 add_delay()

```
void GenericAuto::add_delay (
            int ms )
```

add_delay adds a period where the auto system will simply wait for the specified time

**Parameters**

| | |
|---|---|
| *ms* | how long to wait in milliseconds |

#### 5.32.2.4 run()

```
bool GenericAuto::run (
            bool blocking )
```

The method that runs the autonomous. If 'blocking' is true, then this method will run through every state until it finished.

If blocking is false, then assuming every state is also non-blocking, the method will run through the current state in the list and return immediately.

**Parameters**

| | |
|---|---|
| *blocking* | Whether or not to block the thread until all states have run |

**Returns**

true after all states have finished.

The documentation for this class was generated from the following files:

- include/utils/generic_auto.h
- src/utils/generic_auto.cpp

## 5.33 GraphDrawer Class Reference

**Public Member Functions**

- GraphDrawer (int num_samples, double lower_bound, double upper_bound, std::vector< vex::color > colors, size_t num_series=1)

  *Creates a graph drawer with the specified number of series (each series is a separate line)*
- void add_samples (std::vector< point_t > sample)
- void add_samples (std::vector< double > sample)
- void draw (vex::brain::lcd &screen, int x, int y, int width, int height)

### 5.33.1 Constructor & Destructor Documentation

#### 5.33.1.1 GraphDrawer()

```
GraphDrawer::GraphDrawer (
            int num_samples,
            double lower_bound,
            double upper_bound,
            std::vector< vex::color > colors,
            size_t num_series = 1 )
```

Creates a graph drawer with the specified number of series (each series is a separate line)

**Parameters**

| | |
|---|---|
| *num_samples* | the number of samples to graph at a time (40 will graph the last 40 data points) |
| *lower_bound* | the bottom of the window when displaying (if upper_bound = lower_bound, auto calculate bounds) |
| *upper_bound* | the top of the window when displaying (if upper_bound = lower_bound, auto calculate bounds) |
| *colors* | the colors of the series. must be of size num_series |
| *num_series* | the number of series to graph |

## 5.33.2 Member Function Documentation

### 5.33.2.1 add_samples() [1/2]

```
void GraphDrawer::add_samples (
            std::vector< double > sample )
```

add_samples adds a point to the graph, removing one from the back

**Parameters**

| | |
|---|---|
| *sample* | a y coordinate of the next point to graph, the x coordinate is gotten from vex::timer::system(); (time in ms) |

### 5.33.2.2 add_samples() [2/2]

```
void GraphDrawer::add_samples (
            std::vector< point_t > new_samples )
```

add_samples adds a point to the graph, removing one from the back

**Parameters**

| | |
|---|---|
| *sample* | an x, y coordinate of the next point to graph |

### 5.33.2.3 draw()

```
void GraphDrawer::draw (
            vex::brain::lcd & screen,
            int x,
            int y,
            int width,
            int height )
```

draws the graph to the screen in the constructor

**Parameters**

| | |
|---|---|
| *x* | x position of the top left of the graphed region |

**Parameters**

| | |
|---|---|
| *y* | y position of the top left of the graphed region |
| *width* | the width of the graphed region |
| *height* | the height of the graphed region |

The documentation for this class was generated from the following files:

- include/utils/graph_drawer.h
- src/utils/graph_drawer.cpp

## 5.34 PurePursuit::hermite_point Struct Reference

`#include <pure_pursuit.h>`

### Public Member Functions

- point_t **getPoint** () const
- Vector2D **getTangent** () const

### Public Attributes

- double **x**
- double **y**
- double **dir**
- double **mag**

### 5.34.1 Detailed Description

a position along the hermite path contains a position and orientation information that the robot would be at at this point

The documentation for this struct was generated from the following file:

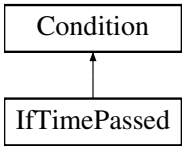
- include/utils/pure_pursuit.h

## 5.35 IfTimePassed Class Reference

IfTimePassed tests based on time since the command controller was constructed. Returns true if elapsed time > time_s.

`#include <auto_command.h>`

Inheritance diagram for IfTimePassed:



**Public Member Functions**

- **IfTimePassed** (double time_s)
- bool test () override

### Public Member Functions inherited from Condition

- Condition * **Or** (Condition *b)
- Condition * **And** (Condition *b)

### 5.35.1 Detailed Description

IfTimePassed tests based on time since the command controller was constructed. Returns true if elapsed time > time_s.

### 5.35.2 Member Function Documentation

#### 5.35.2.1 test()

```
bool IfTimePassed::test ( )  [override], [virtual]
```

Implements Condition.

The documentation for this class was generated from the following files:

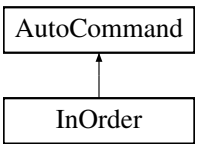
- include/utils/command_structure/auto_command.h
- src/utils/command_structure/auto_command.cpp

## 5.36 InOrder Class Reference

InOrder runs its commands sequentially then continues. How to handle timeout in this case. Automatically set it to sum of commands timouts?

```
#include <auto_command.h>
```

Inheritance diagram for InOrder:




**Public Member Functions**

- **InOrder** (const InOrder &other)=default
- **InOrder** (std::queue< AutoCommand * > cmds)
- **InOrder** (std::initializer_list< AutoCommand * > cmds)
- bool run () override
- void on_timeout () override

## Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Additional Inherited Members

## Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

## Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.36.1 Detailed Description

InOrder runs its commands sequentially then continues. How to handle timeout in this case. Automatically set it to sum of commands timouts?

InOrder runs its commands sequentially then continues. How to handle timeout in this case. Automatically set it to sum of commands timouts?

## 5.36.2 Member Function Documentation

### 5.36.2.1 on_timeout()

```
void InOrder::on_timeout ( )  [override], [virtual]
```

What to do if we timeout instead of finishing. timeout is specified by the timeout seconds in the constructor

Reimplemented from AutoCommand.

### 5.36.2.2 run()

```
bool InOrder::run ( )  [override], [virtual]
```

Executes the command Overridden by child classes

**Returns**

true when the command is finished, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/auto_command.h
- src/utils/command_structure/auto_command.cpp

## 5.37 Lift< T > Class Template Reference

`#include <lift.h>`

### Classes

- struct lift_cfg_t

### Public Member Functions

- Lift (motor_group &lift_motors, lift_cfg_t &lift_cfg, map< T, double > &setpoint_map, limit *homing_switch=NULL)
- void control_continuous (bool up_ctrl, bool down_ctrl)
- void control_manual (bool up_btn, bool down_btn, int volt_up, int volt_down)
- void control_setpoints (bool up_step, bool down_step, vector< T > pos_list)
- bool set_position (T pos)
- bool set_setpoint (double val)
- double get_setpoint ()
- void hold ()
- void home ()
- bool get_async ()
- void set_async (bool val)
- void set_sensor_function (double(*fn_ptr)(void))
- void set_sensor_reset (void(*fn_ptr)(void))

### 5.37.1 Detailed Description

**template<typename T>**
**class Lift< T >**

LIFT A general class for lifts (e.g. 4bar, dr4bar, linear, etc) Uses a PID to hold the lift at a certain height under load, and to move the lift to different heights

**Author**

Ryan McGee

### 5.37.2 Constructor & Destructor Documentation

#### 5.37.2.1 Lift()

```
template<typename T >
Lift< T >::Lift (
            motor_group & lift_motors,
            lift_cfg_t & lift_cfg,
            map< T, double > & setpoint_map,
            limit * homing_switch = NULL )  [inline]
```

Construct the Lift object and begin the background task that controls the lift.

Usage example: /code{.cpp} enum Positions {UP, MID, DOWN}; map<Positions, double> setpt_map { {DOWN, 0.0}, {MID, 0.5}, {UP, 1.0} }; Lift<Positions> my_lift(motors, lift_cfg, setpt_map); /endcode

**Parameters**

| | |
|---|---|
| *lift_motors* | A set of motors, all set that positive rotation correlates with the lift going up |
| *lift_cfg* | Lift characterization information; PID tunings and movement speeds |
| *setpoint_map* | A map of enum type T, in which each enum entry corresponds to a different lift height |

## 5.37.3 Member Function Documentation

### 5.37.3.1 control_continuous()

```
template<typename T >
void Lift< T >::control_continuous (
            bool up_ctrl,
            bool down_ctrl )  [inline]
```

Control the lift with an "up" button and a "down" button. Use PID to hold the lift when letting go.

**Parameters**

| | |
|---|---|
| *up_ctrl* | Button controlling the "UP" motion |
| *down_ctrl* | Button controlling the "DOWN" motion |

### 5.37.3.2 control_manual()

```
template<typename T >
void Lift< T >::control_manual (
            bool up_btn,
            bool down_btn,
            int volt_up,
            int volt_down )  [inline]
```

Control the lift with manual controls (no holding voltage)

**Parameters**

| | |
|---|---|
| *up_btn* | Raise the lift when true |
| *down_btn* | Lower the lift when true |
| *volt_up* | Motor voltage when raising the lift |
| *volt_down* | Motor voltage when lowering the lift |

### 5.37.3.3 control_setpoints()

```
template<typename T >
void Lift< T >::control_setpoints (
            bool up_step,
            bool down_step,
            vector< T > pos_list )  [inline]
```

Control the lift in "steps". When the "up" button is pressed, the lift will go to the next position as defined by pos_list. Order matters!

**Parameters**

| | |
|---|---|
| *up_step* | A button that increments the position of the lift. |
| *down_step* | A button that decrements the position of the lift. |
| *pos_list* | A list of positions for the lift to go through. The higher the index, the higher the lift should be (generally). |

#### 5.37.3.4 get_async()

```
template<typename T >
bool Lift< T >::get_async ( )  [inline]
```

**Returns**

whether or not the background thread is running the lift

#### 5.37.3.5 get_setpoint()

```
template<typename T >
double Lift< T >::get_setpoint ( )  [inline]
```

**Returns**

The current setpoint for the lift

#### 5.37.3.6 hold()

```
template<typename T >
void Lift< T >::hold ( )  [inline]
```

Target the class's setpoint. Calculate the PID output and set the lift motors accordingly.

#### 5.37.3.7 home()

```
template<typename T >
void Lift< T >::home ( )  [inline]
```

A blocking function that automatically homes the lift based on a sensor or hard stop, and sets the position to 0. A watchdog times out after 3 seconds, to avoid damage.

#### 5.37.3.8 set_async()

```
template<typename T >
void Lift< T >::set_async (
            bool val )  [inline]
```

Enables or disables the background task. Note that running the control functions, or set_position functions will immediately re-enable the task for autonomous use.

**Parameters**

| | |
|---|---|
| *val* | Whether or not the background thread should run the lift |

#### 5.37.3.9 set_position()

```
template<typename T >
bool Lift< T >::set_position (
            T pos )  [inline]
```

Enable the background task, and send the lift to a position, specified by the setpoint map from the constructor.

**Parameters**

| | |
|---|---|
| *pos* | A lift position enum type |

**Returns**

True if the pid has reached the setpoint

#### 5.37.3.10 set_sensor_function()

```
template<typename T >
void Lift< T >::set_sensor_function (
            double(*)(void) fn_ptr )  [inline]
```

Creates a custom hook for any other type of sensor to be used on the lift. Example: /code{.cpp} my_lift.set_↩ sensor_function( [](){return my_sensor.position();} ); /endcode

**Parameters**

| | |
|---|---|
| *fn_ptr* | Pointer to custom sensor function |

#### 5.37.3.11 set_sensor_reset()

```
template<typename T >
void Lift< T >::set_sensor_reset (
            void(*)(void) fn_ptr )  [inline]
```

Creates a custom hook to reset the sensor used in set_sensor_function(). Example: /code{.cpp} my_lift.set_↩ sensor_reset( my_sensor.resetPosition ); /endcode

#### 5.37.3.12 set_setpoint()

```
template<typename T >
bool Lift< T >::set_setpoint (
            double val )  [inline]
```

Manually set a setpoint value for the lift PID to go to.

**Parameters**

| | |
|---|---|
| *val* | Lift setpoint, in motor revolutions or sensor units defined by get_sensor. Cannot be outside the softstops. |

**Returns**

True if the pid has reached the setpoint

The documentation for this class was generated from the following file:

- include/subsystems/lift.h

## 5.38 Lift< T >::lift_cfg_t Struct Reference

`#include <lift.h>`

**Public Attributes**

- double **up_speed**
- double **down_speed**
- double **softstop_up**
- double **softstop_down**
- PID::pid_config_t **lift_pid_cfg**

### 5.38.1 Detailed Description

**template<typename T>**
**struct Lift< T >::lift_cfg_t**

lift_cfg_t holds the physical parameter specifications of a lify system. includes:

- maximum speeds for the system
- softstops to stop the lift from hitting the hard stops too hard

The documentation for this struct was generated from the following file:

- include/subsystems/lift.h

## 5.39 Logger Class Reference

Class to simplify writing to files.

`#include <logger.h>`

### Public Member Functions

- Logger (const std::string &filename)
  *Create a logger that will save to a file.*
- **Logger** (const Logger &l)=delete
  *copying not allowed*
- Logger & **operator=** (const Logger &l)=delete
  *copying not allowed*
- void Log (const std::string &s)
  *Write a string to the log.*
- void Log (LogLevel level, const std::string &s)
  *Write a string to the log with a loglevel.*
- void LogIn (const std::string &s)
  *Write a string and newline to the log.*
- void LogIn (LogLevel level, const std::string &s)
  *Write a string and a newline to the log with a loglevel.*
- void Logf (const char *fmt,...)
  *Write a formatted string to the log.*
- void Logf (LogLevel level, const char *fmt,...)
  *Write a formatted string to the log with a loglevel.*

### Static Public Attributes

- static constexpr int **MAX_FORMAT_LEN** = 512
  *maximum size for a string to be before it's written*

## 5.39.1 Detailed Description

Class to simplify writing to files.

## 5.39.2 Constructor & Destructor Documentation

### 5.39.2.1 Logger()

```
Logger::Logger (
            const std::string & filename )  [explicit]
```

Create a logger that will save to a file.

**Parameters**

| | |
|---|---|
| *filename* | the file to save to |

### 5.39.3 Member Function Documentation

#### 5.39.3.1 Log() [1/2]

```
void Logger::Log (
            const std::string & s )
```

Write a string to the log.

**Parameters**

| | |
|---|---|
| *s* | the string to write |

#### 5.39.3.2 Log() [2/2]

```
void Logger::Log (
            LogLevel level,
            const std::string & s )
```

Write a string to the log with a loglevel.

**Parameters**

| | |
|---|---|
| *level* | the level to write. DEBUG, NOTICE, WARNING, ERROR, CRITICAL, TIME |
| *s* | the string to write |

#### 5.39.3.3 Logf() [1/2]

```
void Logger::Logf (
            const char * fmt,
             ...  )
```

Write a formatted string to the log.

**Parameters**

| | |
|---|---|
| *fmt* | the format string (like printf) |
| *...* | the args |

#### 5.39.3.4 Logf() [2/2]

```
void Logger::Logf (
            LogLevel level,
            const char * fmt,
             ...  )
```

Write a formatted string to the log with a loglevel.

**Parameters**

| | |
|---|---|
| *level* | the level to write. DEBUG, NOTICE, WARNING, ERROR, CRITICAL, TIME |
| *fmt* | the format string (like printf) |
| ... | the args |

#### 5.39.3.5 LogIn() [1/2]

```
void Logger::LogIn (
            const std::string & s )
```

Write a string and newline to the log.

**Parameters**

| | |
|---|---|
| *s* | the string to write |

#### 5.39.3.6 LogIn() [2/2]

```
void Logger::LogIn (
            LogLevel level,
            const std::string & s )
```

Write a string and a newline to the log with a loglevel.

**Parameters**

| | |
|---|---|
| *level* | the level to write. DEBUG, NOTICE, WARNING, ERROR, CRITICAL, TIME |
| *s* | the string to write |

The documentation for this class was generated from the following files:

- include/utils/logger.h
- src/utils/logger.cpp

## 5.40 MotionController::m_profile_cfg_t Struct Reference

```
#include <motion_controller.h>
```

### Public Attributes

- double **max_v**

  *the maximum velocity the robot can drive*
- double **accel**

  *the most acceleration the robot can do*
- PID::pid_config_t **pid_cfg**

  *configuration parameters for the internal PID controller*
- FeedForward::ff_config_t **ff_cfg**

  *configuration parameters for the internal*

### 5.40.1 Detailed Description

m_profile_config holds all data the motion controller uses to plan paths When motion pofile is given a target to drive to, max_v and accel are used to make the trapezoid profile instructing the controller how to drive pid_cfg, ff_cfg are used to find the motor outputs necessary to execute this path

The documentation for this struct was generated from the following file:

- include/utils/controls/motion_controller.h

## 5.41 Mat2 Struct Reference

#### Public Member Functions

- point_t **operator**∗ (const point_t p) const

#### Static Public Member Functions

- static Mat2 **FromRotationDegrees** (double degrees)

#### Public Attributes

- double **X11**
- double **X12**
- double **X21**
- double **X22**

The documentation for this struct was generated from the following file:

- include/utils/geometry.h

## 5.42 MecanumDrive Class Reference

```
#include <mecanum_drive.h>
```

#### Classes

- struct mecanumdrive_config_t

#### Public Member Functions

- MecanumDrive (vex::motor &left_front, vex::motor &right_front, vex::motor &left_rear, vex::motor &right_rear, vex::rotation ∗lateral_wheel=NULL, vex::inertial ∗imu=NULL, mecanumdrive_config_t ∗config=NULL)
- void drive_raw (double direction_deg, double magnitude, double rotation)
- void drive (double left_y, double left_x, double right_x, int power=2)
- bool auto_drive (double inches, double direction, double speed, bool gyro_correction=true)
- bool auto_turn (double degrees, double speed, bool ignore_imu=false)

### 5.42.1 Detailed Description

A class representing the Mecanum drivetrain. Contains 4 motors, a possible IMU (intertial), and a possible undriven perpendicular wheel.

### 5.42.2 Constructor & Destructor Documentation

#### 5.42.2.1 MecanumDrive()

```
MecanumDrive::MecanumDrive (
            vex::motor & left_front,
            vex::motor & right_front,
            vex::motor & left_rear,
            vex::motor & right_rear,
            vex::rotation * lateral_wheel = NULL,
            vex::inertial * imu = NULL,
            mecanumdrive_config_t * config = NULL )
```

Create the Mecanum drivetrain object

### 5.42.3 Member Function Documentation

#### 5.42.3.1 auto_drive()

```
bool MecanumDrive::auto_drive (
            double inches,
            double direction,
            double speed,
            bool gyro_correction = true )
```

Drive the robot in a straight line automatically. If the inertial was declared in the constructor, use it to correct while driving. If the lateral wheel was declared in the constructor, use it for more accurate positioning while strafing.

**Parameters**

| | |
|---|---|
| *inches* | How far the robot should drive, in inches |
| *direction* | What direction the robot should travel in, in degrees. 0 is forward, +/-180 is reverse, clockwise is positive. |
| *speed* | The maximum speed the robot should travel, in percent: -1.0->+1.0 |
| *gyro_correction* | =true Whether or not to use the gyro to help correct while driving. Will always be false if no gyro was declared in the constructor. |

Drive the robot in a straight line automatically. If the inertial was declared in the constructor, use it to correct while driving. If the lateral wheel was declared in the constructor, use it for more accurate positioning while strafing.

**Parameters**

| | |
|---|---|
| *inches* | How far the robot should drive, in inches |
| *direction* | What direction the robot should travel in, in degrees. 0 is forward, +/-180 is reverse, clockwise is positive. |

**Parameters**

| | |
|---|---|
| *speed* | The maximum speed the robot should travel, in percent: -1.0->+1.0 |
| *gyro_correction* | = true Whether or not to use the gyro to help correct while driving. Will always be false if no gyro was declared in the constructor. |

**Returns**

Whether or not the maneuver is complete.

#### 5.42.3.2 auto_turn()

```
bool MecanumDrive::auto_turn (
            double degrees,
            double speed,
            bool ignore_imu = false )
```

Autonomously turn the robot X degrees over it's center point. Uses a closed loop for control.

**Parameters**

| | |
|---|---|
| *degrees* | How many degrees to rotate the robot. Clockwise postive. |
| *speed* | What percentage to run the motors at: 0.0 -> 1.0 |
| *ignore_imu* | =false Whether or not to use the Inertial for determining angle. Will instead use circumference formula + robot's wheelbase + encoders to determine. |

**Returns**

whether or not the robot has finished the maneuver

Autonomously turn the robot X degrees over it's center point. Uses a closed loop for control.

**Parameters**

| | |
|---|---|
| *degrees* | How many degrees to rotate the robot. Clockwise postive. |
| *speed* | What percentage to run the motors at: 0.0 -> 1.0 |
| *ignore_imu* | = false Whether or not to use the Inertial for determining angle. Will instead use circumference formula + robot's wheelbase + encoders to determine. |

**Returns**

whether or not the robot has finished the maneuver

#### 5.42.3.3 drive()

```
void MecanumDrive::drive (
            double left_y,
```

```
            double left_x,
            double right_x,
            int power = 2 )
```

Drive the robot with a mecanum-style / arcade drive. Inputs are in percent (-100.0 -> 100.0) straight from the controller. Controls are mixed, so the robot can drive forward / strafe / rotate all at the same time.

**Parameters**

| | |
|---|---|
| *left_y* | left joystick, Y axis (forward / backwards) |
| *left_x* | left joystick, X axis (strafe left / right) |
| *right_x* | right joystick, X axis (rotation left / right) |
| *power* | =2 how much of a "curve" there should be on drive controls; better for low speed maneuvers. Leave blank for a default curve of 2 (higher means more fidelity) |

Drive the robot with a mecanum-style / arcade drive. Inputs are in percent (-100.0 -> 100.0) straight from the controller. Controls are mixed, so the robot can drive forward / strafe / rotate all at the same time.

**Parameters**

| | |
|---|---|
| *left_y* | left joystick, Y axis (forward / backwards) |
| *left_x* | left joystick, X axis (strafe left / right) |
| *right_x* | right joystick, X axis (rotation left / right) |
| *power* | = 2 how much of a "curve" there should be on drive controls; better for low speed maneuvers. Leave blank for a default curve of 2 (higher means more fidelity) |

#### 5.42.3.4 drive_raw()

```
void MecanumDrive::drive_raw (
            double direction_deg,
            double magnitude,
            double rotation )
```

Drive the robot using vectors. This handles all the math required for mecanum control.

**Parameters**

| | |
|---|---|
| *direction_deg* | the direction to drive the robot, in degrees. 0 is forward, 180 is back, clockwise is positive, counterclockwise is negative. |
| *magnitude* | How fast the robot should drive, in percent: 0.0->1.0 |
| *rotation* | How fast the robot should rotate, in percent: -1.0->+1.0 |

The documentation for this class was generated from the following files:

- include/subsystems/mecanum_drive.h
- src/subsystems/mecanum_drive.cpp

## 5.43 MecanumDrive::mecanumdrive_config_t Struct Reference

`#include <mecanum_drive.h>`

### Public Attributes

- PID::pid_config_t **drive_pid_conf**
- PID::pid_config_t **drive_gyro_pid_conf**
- PID::pid_config_t **turn_pid_conf**
- double **drive_wheel_diam**
- double **lateral_wheel_diam**
- double **wheelbase_width**

### 5.43.1 Detailed Description

Configure the Mecanum drive PID tunings and robot configurations

The documentation for this struct was generated from the following file:

- include/subsystems/mecanum_drive.h

## 5.44 motion_t Struct Reference

`#include <trapezoid_profile.h>`

### Public Attributes

- double **pos**
  *1d position at this point in time*
- double **vel**
  *1d velocity at this point in time*
- double **accel**
  *1d acceleration at this point in time*

### 5.44.1 Detailed Description

motion_t is a description of 1 dimensional motion at a point in time.

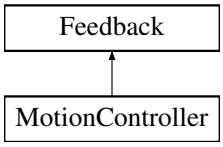
The documentation for this struct was generated from the following file:

- include/utils/controls/trapezoid_profile.h

## 5.45 MotionController Class Reference

`#include <motion_controller.h>`

Inheritance diagram for MotionController:




### Classes

- struct m_profile_cfg_t

### Public Member Functions

- MotionController (m_profile_cfg_t &config)

  *Construct a new Motion Controller object.*
- void init (double start_pt, double end_pt, double start_vel, double end_vel) override

  *Initialize the motion profile for a new movement This will also reset the PID and profile timers.*
- double update (double sensor_val) override

  *Update the motion profile with a new sensor value.*
- double get () override
- void set_limits (double lower, double upper) override
- bool is_on_target () override
- motion_t get_motion ()

### Static Public Member Functions

- static FeedForward::ff_config_t tune_feedforward (TankDrive &drive, OdometryTank &odometry, double pct=0.6, double duration=2)

### 5.45.1 Detailed Description

Motion Controller class

This class defines a top-level motion profile, which can act as an intermediate between a subsystem class and the motors themselves

This takes the constants kS, kV, kA, kP, kI, kD, max_v and acceleration and wraps around a feedforward, PID and trapezoid profile. It does so with the following formula:

out = feedfoward.calculate(motion_profile.get(time_s)) + pid.get(motion_profile.get(time_s))

For PID and Feedforward specific formulae, see pid.h, feedforward.h, and trapezoid_profile.h

**Author**

Ryan McGee

**Date**

7/13/2022

## 5.45.2 Constructor & Destructor Documentation

### 5.45.2.1 MotionController()

```
MotionController::MotionController (
            m_profile_cfg_t & config )
```

Construct a new Motion Controller object.

**Parameters**

| | |
|---|---|
| *config* | The definition of how the robot is able to move max_v Maximum velocity the movement is capable of accel Acceleration / deceleration of the movement pid_cfg Definitions of kP, kI, and kD ff_cfg Definitions of kS, kV, and kA |

## 5.45.3 Member Function Documentation

### 5.45.3.1 get()

```
double MotionController::get ( )  [override], [virtual]
```

**Returns**

the last saved result from the feedback controller

Implements Feedback.

### 5.45.3.2 get_motion()

```
motion_t MotionController::get_motion ( )
```

**Returns**

The current postion, velocity and acceleration setpoints

### 5.45.3.3 init()

```
void MotionController::init (
            double start_pt,
            double end_pt,
            double start_vel,
            double end_vel )  [override], [virtual]
```

Initialize the motion profile for a new movement This will also reset the PID and profile timers.

**Parameters**

| | |
|---|---|
| *start_pt* | Movement starting position |
| *end_pt* | Movement ending posiiton |
| *start_vel* | Movement starting velocity |
| *end_vel* | Movement ending velocity |

Implements Feedback.

#### 5.45.3.4 is_on_target()

```
bool MotionController::is_on_target ( )  [override], [virtual]
```

**Returns**

Whether or not the movement has finished, and the PID confirms it is on target

Implements Feedback.

#### 5.45.3.5 set_limits()

```
void MotionController::set_limits (
            double lower,
            double upper )  [override], [virtual]
```

Clamp the upper and lower limits of the output. If both are 0, no limits should be applied. if limits are applied, the controller will not target any value below lower or above upper

**Parameters**

| | |
|---|---|
| *lower* | upper limit |
| *upper* | lower limiet |

Clamp the upper and lower limits of the output. If both are 0, no limits should be applied.

**Parameters**

| | |
|---|---|
| *lower* | Upper limit |
| *upper* | Lower limit |

Implements Feedback.

#### 5.45.3.6 tune_feedforward()

```
FeedForward::ff_config_t MotionController::tune_feedforward (
            TankDrive & drive,
            OdometryTank & odometry,
            double pct = 0.6,
            double duration = 2 )  [static]
```

This method attempts to characterize the robot's drivetrain and automatically tune the feedforward. It does this by first calculating the kS (voltage to overcome static friction) by slowly increasing the voltage until it moves.

Next is kV (voltage to sustain a certain velocity), where the robot will record it's steady-state velocity at 'pct' speed.

Finally, kA (voltage needed to accelerate by a certain rate), where the robot will record the entire movement's velocity and acceleration, record a plot of [X=(pct-kV∗V-kS), Y=(Acceleration)] along the movement, and since kA∗Accel = pct-kV∗V-kS, the reciprocal of the linear regression is the kA value.

**Parameters**

| | |
|---|---|
| *drive* | The tankdrive to operate on |
| *odometry* | The robot's odometry subsystem |
| *pct* | Maximum velocity in percent (0->1.0) |
| *duration* | Amount of time the robot should be moving for the test |

**Returns**

A tuned feedforward object

#### 5.45.3.7 update()

```
double MotionController::update (
            double sensor_val )  [override], [virtual]
```

Update the motion profile with a new sensor value.

**Parameters**

| | |
|---|---|
| *sensor_val* | Value from the sensor |

**Returns**

the motor input generated from the motion profile

Implements Feedback.

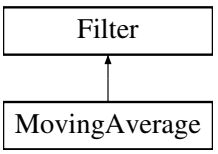
The documentation for this class was generated from the following files:

- include/utils/controls/motion_controller.h
- src/utils/controls/motion_controller.cpp

## 5.46 MovingAverage Class Reference

```
#include <moving_average.h>
```

Inheritance diagram for MovingAverage:



**Public Member Functions**

- MovingAverage (int buffer_size)
- MovingAverage (int buffer_size, double starting_value)
- void add_entry (double n)
- double get_value () const
- int get_size () const

## 5.46.1 Detailed Description

MovingAverage

A moving average is a way of smoothing out noisy data. For many sensor readings, the noise is roughly symmetric around the actual value. This means that if you collect enough samples those that are too high are cancelled out by the samples that are too low leaving the real value.

The MovingAverage class provides a simple interface to do this smoothing from our noisy sensor values.

WARNING: because we need a lot of samples to get the actual value, the value given by the MovingAverage will 'lag' behind the actual value that the sensor is reading. Using a MovingAverage is thus a tradeoff between accuracy and lag time (more samples) vs. less accuracy and faster updating (less samples).

## 5.46.2 Constructor & Destructor Documentation

### 5.46.2.1 MovingAverage() [1/2]

```
MovingAverage::MovingAverage (
            int buffer_size )
```

Create a moving average calculator with 0 as the default value

**Parameters**

| | |
|---|---|
| *buffer_size* | The size of the buffer. The number of samples that constitute a valid reading |

### 5.46.2.2 MovingAverage() [2/2]

```
MovingAverage::MovingAverage (
            int buffer_size,
            double starting_value )
```

Create a moving average calculator with a specified default value

**Parameters**

| | |
|---|---|
| *buffer_size* | The size of the buffer. The number of samples that constitute a valid reading |
| *starting_value* | The value that the average will be before any data is added |

### 5.46.3 Member Function Documentation

#### 5.46.3.1 add_entry()

```
void MovingAverage::add_entry (
            double n )  [virtual]
```

Add a reading to the buffer Before: [ 1 1 2 2 3 3] => 2 ^ After: [ 2 1 2 2 3 3] => 2.16 ^

**Parameters**

| | |
|---|---|
| *n* | the sample that will be added to the moving average. |

Implements Filter.

#### 5.46.3.2 get_size()

```
int MovingAverage::get_size ( ) const
```

How many samples the average is made from

**Returns**

the number of samples used to calculate this average

#### 5.46.3.3 get_value()

```
double MovingAverage::get_value ( ) const  [virtual]
```

Returns the average based off of all the samples collected so far

**Returns**

the calculated average. sum(samples)/numsamples

How many samples the average is made from

**Returns**

the number of samples used to calculate this average

Implements Filter.

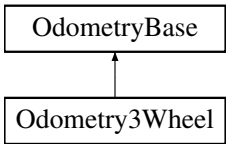
The documentation for this class was generated from the following files:

- include/utils/moving_average.h
- src/utils/moving_average.cpp

# 5.47 Odometry3Wheel Class Reference

`#include <odometry_3wheel.h>`

Inheritance diagram for Odometry3Wheel:




### Classes

- struct odometry3wheel_cfg_t

### Public Member Functions

- Odometry3Wheel (CustomEncoder &lside_fwd, CustomEncoder &rside_fwd, CustomEncoder &off_axis, odometry3wheel_cfg_t &cfg, bool is_async=true)
- pose_t update () override
- void tune (vex::controller &con, TankDrive &drive)

## Public Member Functions inherited from OdometryBase

- OdometryBase (bool is_async)
- pose_t get_position (void)
- virtual void set_position (const pose_t &newpos=zero_pos)
- void end_async ()
- double get_speed ()
- double get_accel ()
- double get_angular_speed_deg ()
- double get_angular_accel_deg ()

### Additional Inherited Members

## Static Public Member Functions inherited from OdometryBase

- static int background_task (void *ptr)
- static double pos_diff (pose_t start_pos, pose_t end_pos)
- static double rot_diff (pose_t pos1, pose_t pos2)
- static double smallest_angle (double start_deg, double end_deg)

## Public Attributes inherited from OdometryBase

- bool **end_task** = false

  *end_task is true if we instruct the odometry thread to shut down*

### Static Public Attributes inherited from OdometryBase

- static constexpr pose_t zero_pos = {.x=0.0L, .y=0.0L, .rot=90.0L}

### Protected Attributes inherited from OdometryBase

- vex::task * handle
- vex::mutex mut
- pose_t current_pos
- double speed
- double accel
- double ang_speed_deg
- double ang_accel_deg

## 5.47.1 Detailed Description

Odometry3Wheel

This class handles the code for a standard 3-pod odometry setup, where there are 3 "pods" made up of undriven (dead) wheels connected to encoders in the following configuration:

+Y ----------— ^ | | | | | | | || O || | | | | | | | === | | ----------— | +------------------> + X

Where O is the center of rotation. The robot will monitor the changes in rotation of these wheels and calculate the robot's X, Y and rotation on the field.

This is a "set and forget" class, meaning once the object is created, the robot will immediately begin tracking it's movement in the background.

**Author**

Ryan McGee

**Date**

Oct 31 2022

## 5.47.2 Constructor & Destructor Documentation

### 5.47.2.1 Odometry3Wheel()

```
Odometry3Wheel::Odometry3Wheel (
            CustomEncoder & lside_fwd,
            CustomEncoder & rside_fwd,
            CustomEncoder & off_axis,
            odometry3wheel_cfg_t & cfg,
            bool is_async = true )
```

Construct a new Odometry 3 Wheel object

**Parameters**

| | |
|---|---|
| *lside_fwd* | left-side encoder reference |
| *rside_fwd* | right-side encoder reference |
| *off_axis* | off-axis (perpendicular) encoder reference |
| *cfg* | robot odometry configuration |
| *is_async* | true to constantly run in the background |

## 5.47.3 Member Function Documentation

### 5.47.3.1 tune()

```
void Odometry3Wheel::tune (
            vex::controller & con,
            TankDrive & drive )
```

A guided tuning process to automatically find tuning parameters. This method is blocking, and returns when tuning has finished. Follow the instructions on the controller to complete the tuning process

**Parameters**

| | |
|---|---|
| *con* | Controller reference, for screen and button control |
| *drive* | Drivetrain reference for robot control |

A guided tuning process to automatically find tuning parameters. This method is blocking, and returns when tuning has finished. Follow the instructions on the controller to complete the tuning process

It is assumed the gear ratio and encoder PPR have been set correctly

### 5.47.3.2 update()

```
pose_t Odometry3Wheel::update ( )  [override], [virtual]
```

Update the current position of the robot once, using the current state of the encoders and the previous known location

**Returns**

the robot's updated position

Implements OdometryBase.

The documentation for this class was generated from the following files:

- include/subsystems/odometry/odometry_3wheel.h
- src/subsystems/odometry/odometry_3wheel.cpp

## 5.48 Odometry3Wheel::odometry3wheel_cfg_t Struct Reference

`#include <odometry_3wheel.h>`

### Public Attributes

- double wheelbase_dist
- double off_axis_center_dist
- double wheel_diam

### 5.48.1 Detailed Description

odometry3wheel_cfg_t holds all the specifications for how to calculate position with 3 encoders See the core wiki for what exactly each of these parameters measures

### 5.48.2 Member Data Documentation

#### 5.48.2.1 off_axis_center_dist

`double Odometry3Wheel::odometry3wheel_cfg_t::off_axis_center_dist`

distance from the center of the robot to the center off axis wheel

#### 5.48.2.2 wheel_diam

`double Odometry3Wheel::odometry3wheel_cfg_t::wheel_diam`

the diameter of the tracking wheel

#### 5.48.2.3 wheelbase_dist

`double Odometry3Wheel::odometry3wheel_cfg_t::wheelbase_dist`

distance from the center of the left wheel to the center of the right wheel

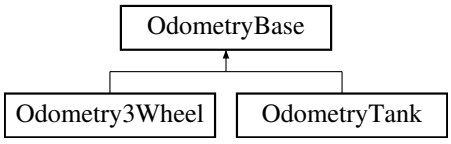
The documentation for this struct was generated from the following file:

- include/subsystems/odometry/odometry_3wheel.h

## 5.49 OdometryBase Class Reference

`#include <odometry_base.h>`

Inheritance diagram for OdometryBase:



### Public Member Functions

- OdometryBase (bool is_async)
- pose_t get_position (void)
- virtual void set_position (const pose_t &newpos=zero_pos)
- virtual pose_t update ()=0
- void end_async ()
- double get_speed ()
- double get_accel ()
- double get_angular_speed_deg ()
- double get_angular_accel_deg ()

### Static Public Member Functions

- static int background_task (void *ptr)
- static double pos_diff (pose_t start_pos, pose_t end_pos)
- static double rot_diff (pose_t pos1, pose_t pos2)
- static double smallest_angle (double start_deg, double end_deg)

### Public Attributes

- bool **end_task** = false

  *end_task is true if we instruct the odometry thread to shut down*

### Static Public Attributes

- static constexpr pose_t zero_pos = {.x=0.0L, .y=0.0L, .rot=90.0L}

### Protected Attributes

- vex::task * handle
- vex::mutex mut
- pose_t current_pos
- double speed
- double accel
- double ang_speed_deg
- double ang_accel_deg

## 5.49.1 Detailed Description

OdometryBase

This base class contains all the shared code between different implementations of odometry. It handles the asynchronous management, position input/output and basic math functions, and holds positional types specific to field orientation.

All future odometry implementations should extend this file and redefine update() function.

**Author**

Ryan McGee

**Date**

Aug 11 2021

## 5.49.2 Constructor & Destructor Documentation

### 5.49.2.1 OdometryBase()

```
OdometryBase::OdometryBase (
            bool is_async )
```

Construct a new Odometry Base object

**Parameters**

| | |
|---|---|
| *is_async* | True to run constantly in the background, false to call update() manually |

## 5.49.3 Member Function Documentation

### 5.49.3.1 background_task()

```
int OdometryBase::background_task (
            void * ptr )  [static]
```

Function that runs in the background task. This function pointer is passed to the vex::task constructor.

**Parameters**

| | |
|---|---|
| *ptr* | Pointer to OdometryBase object |

**Returns**

Required integer return code. Unused.

### 5.49.3.2 end_async()

```
void OdometryBase::end_async ( )
```

End the background task. Cannot be restarted. If the user wants to end the thread but keep the data up to date, they must run the update() function manually from then on.

### 5.49.3.3 get_accel()

```
double OdometryBase::get_accel ( )
```

Get the current acceleration

**Returns**

the acceleration rate of the robot (inch/s^2)

#### 5.49.3.4 get_angular_accel_deg()

```
double OdometryBase::get_angular_accel_deg ( )
```

Get the current angular acceleration in degrees

**Returns**

the angular acceleration at which we are turning (deg/s^2)

#### 5.49.3.5 get_angular_speed_deg()

```
double OdometryBase::get_angular_speed_deg ( )
```

Get the current angular speed in degrees

**Returns**

the angular velocity at which we are turning (deg/s)

#### 5.49.3.6 get_position()

```
pose_t OdometryBase::get_position (
            void  )
```

Gets the current position and rotation

**Returns**

the position that the odometry believes the robot is at

Gets the current position and rotation

#### 5.49.3.7 get_speed()

```
double OdometryBase::get_speed ( )
```

Get the current speed

**Returns**

the speed at which the robot is moving and grooving (inch/s)

#### 5.49.3.8 pos_diff()

```
double OdometryBase::pos_diff (
            pose_t start_pos,
            pose_t end_pos )  [static]
```

Get the distance between two points

**Parameters**

| | |
|---|---|
| *start_pos* | distance from this point |
| *end_pos* | to this point |

**Returns**

the euclidean distance between start_pos and end_pos

#### 5.49.3.9 rot_diff()

```
double OdometryBase::rot_diff (
            pose_t pos1,
            pose_t pos2 )  [static]
```

Get the change in rotation between two points

**Parameters**

| | |
|---|---|
| *pos1* | position with initial rotation |
| *pos2* | position with final rotation |

**Returns**

change in rotation between pos1 and pos2

Get the change in rotation between two points

#### 5.49.3.10 set_position()

```
void OdometryBase::set_position (
            const pose_t & newpos = zero_pos )  [virtual]
```

Sets the current position of the robot

**Parameters**

| | |
|---|---|
| *newpos* | the new position that the odometry will believe it is at |

Sets the current position of the robot

Reimplemented in OdometryTank.

#### 5.49.3.11 smallest_angle()

```
double OdometryBase::smallest_angle (
            double start_deg,
            double end_deg )  [static]
```

Get the smallest difference in angle between a start heading and end heading. Returns the difference between -180 degrees and +180 degrees, representing the robot turning left or right, respectively.

**Parameters**

| | |
|---|---|
| *start_deg* | intitial angle (degrees) |
| *end_deg* | final angle (degrees) |

**Returns**

the smallest angle from the initial to the final angle. This takes into account the wrapping of rotations around 360 degrees

Get the smallest difference in angle between a start heading and end heading. Returns the difference between -180 degrees and +180 degrees, representing the robot turning left or right, respectively.

#### 5.49.3.12 update()

```
virtual pose_t OdometryBase::update ( )  [pure virtual]
```

Update the current position on the field based on the sensors

**Returns**

the location that the robot is at after the odometry does its calculations

Implemented in Odometry3Wheel, and OdometryTank.

### 5.49.4 Member Data Documentation

#### 5.49.4.1 accel

```
double OdometryBase::accel  [protected]
```

the rate at which we are accelerating (inch/s^2)

#### 5.49.4.2 ang_accel_deg

```
double OdometryBase::ang_accel_deg  [protected]
```

the rate at which we are accelerating our turn (deg/s^2)

#### 5.49.4.3 ang_speed_deg

```
double OdometryBase::ang_speed_deg  [protected]
```

the speed at which we are turning (deg/s)

#### 5.49.4.4 current_pos

```
pose_t OdometryBase::current_pos  [protected]
```

Current position of the robot in terms of x,y,rotation

#### 5.49.4.5 handle

```
vex::task* OdometryBase::handle  [protected]
```

handle to the vex task that is running the odometry code

#### 5.49.4.6 mut

```
vex::mutex OdometryBase::mut  [protected]
```

Mutex to control multithreading

#### 5.49.4.7 speed

```
double OdometryBase::speed  [protected]
```

the speed at which we are travelling (inch/s)

#### 5.49.4.8 zero_pos

```
constexpr pose_t OdometryBase::zero_pos = {.x=0.0L, .y=0.0L, .rot=90.0L}  [inline], [static],
[constexpr]
```

Zeroed position. X=0, Y=0, Rotation= 90 degrees

The documentation for this class was generated from the following files:

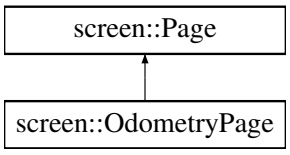
- include/subsystems/odometry/odometry_base.h
- src/subsystems/odometry/odometry_base.cpp

## 5.50 screen::OdometryPage Class Reference

a page that shows odometry position and rotation and a map (if an sd card with the file is on)

```
#include <screen.h>
```

Inheritance diagram for screen::OdometryPage:



**Public Member Functions**

- OdometryPage (OdometryBase &odom, double robot_width, double robot_height, bool do_trail)
  *Create an odometry trail. Make sure odometry is initilized before now.*
- void update (bool was_pressed, int x, int y) override
- void draw (vex::brain::lcd &, bool first_draw, unsigned int frame_number) override

## 5.50.1 Detailed Description

a page that shows odometry position and rotation and a map (if an sd card with the file is on)

## 5.50.2 Constructor & Destructor Documentation

### 5.50.2.1 OdometryPage()

```
screen::OdometryPage::OdometryPage (
            OdometryBase & odom,
            double robot_width,
            double robot_height,
            bool do_trail )
```

Create an odometry trail. Make sure odometry is initilized before now.

**Parameters**

| | |
|---|---|
| *odom* | the odometry system to monitor |
| *robot_width* | the width (side to side) of the robot in inches. Used for visualization |
| *robot_height* | the robot_height (front to back) of the robot in inches. Used for visualization |
| *do_trail* | whether or not to calculate and draw the trail. Drawing and storing takes a very *slight* extra amount of processing power |

## 5.50.3 Member Function Documentation

### 5.50.3.1 draw()

```
void screen::OdometryPage::draw (
            vex::brain::lcd & scr,
            bool first_draw,
            unsigned int frame_number )  [override], [virtual]
```

**See also**

Page::draw

Reimplemented from screen::Page.

#### 5.50.3.2 update()

```
void screen::OdometryPage::update (
            bool was_pressed,
            int x,
            int y )  [override], [virtual]
```

**See also**

Page::update

Reimplemented from screen::Page.

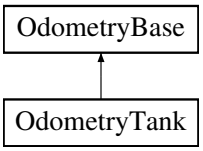
The documentation for this class was generated from the following files:

- include/subsystems/screen.h
- src/subsystems/screen.cpp

## 5.51 OdometryTank Class Reference

`#include <odometry_tank.h>`

Inheritance diagram for OdometryTank:




### Public Member Functions

- OdometryTank (vex::motor_group &left_side, vex::motor_group &right_side, robot_specs_t &config, vex↩ ::inertial *imu=NULL, bool is_async=true)
- OdometryTank (CustomEncoder &left_custom_enc, CustomEncoder &right_custom_enc, robot_specs_t &config, vex::inertial *imu=NULL, bool is_async=true)
- OdometryTank (vex::encoder &left_vex_enc, vex::encoder &right_vex_enc, robot_specs_t &config, vex↩ ::inertial *imu=NULL, bool is_async=true)
- pose_t update () override
- void set_position (const pose_t &newpos=zero_pos) override

### Public Member Functions inherited from OdometryBase

- OdometryBase (bool is_async)
- pose_t get_position (void)
- void end_async ()
- double get_speed ()
- double get_accel ()
- double get_angular_speed_deg ()
- double get_angular_accel_deg ()

**Additional Inherited Members**

### Static Public Member Functions inherited from OdometryBase

- static int background_task (void *ptr)
- static double pos_diff (pose_t start_pos, pose_t end_pos)
- static double rot_diff (pose_t pos1, pose_t pos2)
- static double smallest_angle (double start_deg, double end_deg)

### Public Attributes inherited from OdometryBase

- bool **end_task** = false

  *end_task is true if we instruct the odometry thread to shut down*

### Static Public Attributes inherited from OdometryBase

- static constexpr pose_t zero_pos = {.x=0.0L, .y=0.0L, .rot=90.0L}

### Protected Attributes inherited from OdometryBase

- vex::task * handle
- vex::mutex mut
- pose_t current_pos
- double speed
- double accel
- double ang_speed_deg
- double ang_accel_deg

## 5.51.1 Detailed Description

OdometryTank defines an odometry system for a tank drivetrain This requires encoders in the same orientation as the drive wheels Odometry is a "start and forget" subsystem, which means once it's created and configured, it will constantly run in the background and track the robot's X, Y and rotation coordinates.

## 5.51.2 Constructor & Destructor Documentation

### 5.51.2.1 OdometryTank() [1/3]

```
OdometryTank::OdometryTank (
            vex::motor_group & left_side,
            vex::motor_group & right_side,
            robot_specs_t & config,
            vex::inertial * imu = NULL,
            bool is_async = true )
```

Initialize the Odometry module, calculating position from the drive motors.

**Parameters**

| | |
|---|---|
| *left_side* | The left motors |
| *right_side* | The right motors |
| *config* | the specifications that supply the odometry with descriptions of the robot. See robot_specs_t for what is contained |
| *imu* | The robot's inertial sensor. If not included, rotation is calculated from the encoders. |
| *is_async* | If true, position will be updated in the background continuously. If false, the programmer will have to manually call update(). |

#### 5.51.2.2 OdometryTank() [2/3]

```
OdometryTank::OdometryTank (
            CustomEncoder & left_custom_enc,
            CustomEncoder & right_custom_enc,
            robot_specs_t & config,
            vex::inertial * imu = NULL,
            bool is_async = true )
```

Initialize the Odometry module, calculating position from the drive motors.

**Parameters**

| | |
|---|---|
| *left_custom_enc* | The left custom encoder |
| *right_custom_enc* | The right custom encoder |
| *config* | the specifications that supply the odometry with descriptions of the robot. See robot_specs_t for what is contained |
| *imu* | The robot's inertial sensor. If not included, rotation is calculated from the encoders. |
| *is_async* | If true, position will be updated in the background continuously. If false, the programmer will have to manually call update(). |

#### 5.51.2.3 OdometryTank() [3/3]

```
OdometryTank::OdometryTank (
            vex::encoder & left_vex_enc,
            vex::encoder & right_vex_enc,
            robot_specs_t & config,
            vex::inertial * imu = NULL,
            bool is_async = true )
```

Initialize the Odometry module, calculating position from the drive motors.

**Parameters**

| | |
|---|---|
| *left_vex_enc* | The left vex encoder |
| *right_vex_enc* | The right vex encoder |
| *config* | the specifications that supply the odometry with descriptions of the robot. See robot_specs_t for what is contained |
| *imu* | The robot's inertial sensor. If not included, rotation is calculated from the encoders. |
| *is_async* | If true, position will be updated in the background continuously. If false, the programmer will have to manually call update(). |

### 5.51.3 Member Function Documentation

#### 5.51.3.1 set_position()

```
void OdometryTank::set_position (
            const pose_t & newpos = zero_pos )  [override], [virtual]
```

set_position tells the odometry to place itself at a position

**Parameters**

| | |
|---|---|
| *newpos* | the position the odometry will take |

Resets the position and rotational data to the input.

Reimplemented from OdometryBase.

#### 5.51.3.2 update()

```
pose_t OdometryTank::update ( )  [override], [virtual]
```

Update the current position on the field based on the sensors

**Returns**

the position that odometry has calculated itself to be at

Update, store and return the current position of the robot. Only use if not initializing with a separate thread.

Implements OdometryBase.

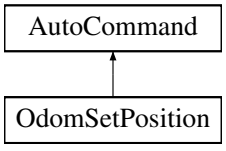
The documentation for this class was generated from the following files:

- include/subsystems/odometry/odometry_tank.h
- src/subsystems/odometry/odometry_tank.cpp

## 5.52 OdomSetPosition Class Reference

```
#include <drive_commands.h>
```

Inheritance diagram for OdomSetPosition:



#### Public Member Functions

- OdomSetPosition (OdometryBase &odom, const pose_t &newpos=OdometryBase::zero_pos)
- bool run () override

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.52.1 Detailed Description

AutoCommand wrapper class for the set_position function in the Odometry class

## 5.52.2 Constructor & Destructor Documentation

### 5.52.2.1 OdomSetPosition()

```
OdomSetPosition::OdomSetPosition (
            OdometryBase & odom,
            const pose_t & newpos = OdometryBase::zero_pos )
```

constructs a new OdomSetPosition command

**Parameters**

| | |
|---|---|
| *odom* | the odometry system we are setting |
| *newpos* | the position we are telling the odometry to take. defaults to (0, 0), angle = 90 |

Construct an Odometry set pos

**Parameters**

| | |
|---|---|
| *odom* | the odometry system we are setting |
| *newpos* | the now position to set the odometry to |

### 5.52.3 Member Function Documentation

#### 5.52.3.1 run()

```
bool OdomSetPosition::run ( )  [override], [virtual]
```

Run set_position Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

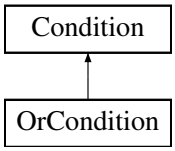
Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/drive_commands.h
- src/utils/command_structure/drive_commands.cpp

## 5.53 OrCondition Class Reference

Inheritance diagram for OrCondition:




**Public Member Functions**

- **OrCondition** (Condition *A, Condition *B)
- bool test () override

### Public Member Functions inherited from Condition

- Condition * **Or** (Condition *b)
- Condition * **And** (Condition *b)

### 5.53.1 Member Function Documentation

#### 5.53.1.1 test()

```
bool OrCondition::test ( )  [inline], [override], [virtual]
```

Implements Condition.

The documentation for this class was generated from the following file:

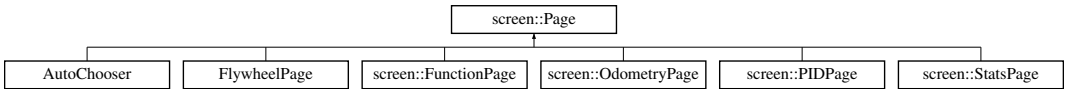
- src/utils/command_structure/auto_command.cpp

## 5.54 screen::Page Class Reference

Page describes one part of the screen slideshow.

`#include <screen.h>`

Inheritance diagram for screen::Page:




### Public Member Functions

- virtual void update (bool was_pressed, int x, int y)

  *collect data, respond to screen input, do fast things (runs at 50hz even if you're not focused on this Page (only drawn page gets touch updates))*
- virtual void draw (vex::brain::lcd &screen, bool first_draw, unsigned int frame_number)

  *draw stored data to the screen (runs at 10 hz and only runs if this page is in front)*

### 5.54.1 Detailed Description

Page describes one part of the screen slideshow.

### 5.54.2 Member Function Documentation

#### 5.54.2.1 draw()

```
virtual void screen::Page::draw (
            vex::brain::lcd & screen,
            bool first_draw,
            unsigned int frame_number )  [virtual]
```

draw stored data to the screen (runs at 10 hz and only runs if this page is in front)

**Parameters**

| | |
|---|---|
| *first_draw* | true if we just switched to this page |
| *frame_number* | frame of drawing we are on (basically an animation tick) |

Reimplemented in AutoChooser, screen::StatsPage, screen::OdometryPage, screen::FunctionPage, screen::PIDPage, and FlywheelPage.

#### 5.54.2.2 update()

```
virtual void screen::Page::update (
            bool was_pressed,
```

```
int x,
int y )  [virtual]
```

collect data, respond to screen input, do fast things (runs at 50hz even if you're not focused on this Page (only drawn page gets touch updates))

**Parameters**

| | |
|---|---|
| *was_pressed* | true if the screen has been pressed |
| *x* | x position of screen press (if the screen was pressed) |
| *y* | y position of screen press (if the screen was pressed) |

Reimplemented in AutoChooser, screen::StatsPage, screen::OdometryPage, screen::FunctionPage, screen::PIDPage, and FlywheelPage.

The documentation for this class was generated from the following file:

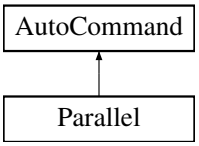
- include/subsystems/screen.h

## 5.55 Parallel Class Reference

Parallel runs multiple commands in parallel and waits for all to finish before continuing. if none finish before this command's timeout, it will call on_timeout on all children continue.

`#include <auto_command.h>`

Inheritance diagram for Parallel:




### Public Member Functions

- **Parallel** (std::initializer_list< AutoCommand * > cmds)
- bool run () override
- void on_timeout () override

### Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.55.1 Detailed Description

Parallel runs multiple commands in parallel and waits for all to finish before continuing. if none finish before this command's timeout, it will call on_timeout on all children continue.

### 5.55.2 Member Function Documentation

#### 5.55.2.1 on_timeout()

```
void Parallel::on_timeout ( )  [override], [virtual]
```

What to do if we timeout instead of finishing. timeout is specified by the timeout seconds in the constructor

Reimplemented from AutoCommand.

#### 5.55.2.2 run()

```
bool Parallel::run ( )  [override], [virtual]
```

Executes the command Overridden by child classes

**Returns**

true when the command is finished, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/auto_command.h
- src/utils/command_structure/auto_command.cpp

## 5.56 parallel_runner_info Struct Reference

### Public Attributes

- int **index**
- std::vector< vex::task * > * **runners**
- AutoCommand * **cmd**

The documentation for this struct was generated from the following file:

- src/utils/command_structure/auto_command.cpp

# 5.57 PurePursuit::Path Class Reference

`#include <pure_pursuit.h>`

### Public Member Functions

- Path (std::vector< point_t > points, double radius)
- std::vector< point_t > get_points ()
- double get_radius ()
- bool is_valid ()

## 5.57.1 Detailed Description

Wrapper for a vector of points, checking if any of the points are too close for pure pursuit

## 5.57.2 Constructor & Destructor Documentation

### 5.57.2.1 Path()

```
PurePursuit::Path::Path (
            std::vector< point_t > points,
            double radius )
```

Create a Path

**Parameters**

| | |
|---|---|
| *points* | the points that make up the path |
| *radius* | the lookahead radius for pure pursuit |

## 5.57.3 Member Function Documentation

### 5.57.3.1 get_points()

```
std::vector< point_t > PurePursuit::Path::get_points ( )
```

Get the points associated with this Path

### 5.57.3.2 get_radius()

```
double PurePursuit::Path::get_radius ( )
```

Get the radius associated with this Path

#### 5.57.3.3 is_valid()

```
bool PurePursuit::Path::is_valid ( )
```

Get whether this path will behave as expected

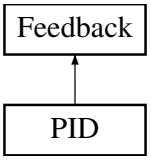
The documentation for this class was generated from the following files:

- include/utils/pure_pursuit.h
- src/utils/pure_pursuit.cpp

## 5.58 PID Class Reference

```
#include <pid.h>
```

Inheritance diagram for PID:




### Classes

- struct pid_config_t

### Public Types

- enum ERROR_TYPE { **LINEAR** , **ANGULAR** }

### Public Member Functions

- PID (pid_config_t &config)
- void init (double start_pt, double set_pt, double start_vel=0, double end_vel=0) override
- double update (double sensor_val) override
- double get_sensor_val ()

  *gets the sensor value that we were last updated with*
- double get () override
- void set_limits (double lower, double upper) override
- bool is_on_target () override
- void reset ()
- double get_error ()
- double get_target ()
- void set_target (double target)

**Public Attributes**

- pid_config_t & **config**
  *configuration struct for this controller. see pid_config_t for information about what this contains*

## 5.58.1 Detailed Description

PID Class

Defines a standard feedback loop using the constants kP, kI, kD, deadband, and on_target_time. The formula is:

out = kP∗error + kI∗integral(d Error) + kD∗(dError/dt)

The PID object will determine it is "on target" when the error is within the deadband, for a duration of on_target_time

**Author**

Ryan McGee

**Date**

4/3/2020

## 5.58.2 Member Enumeration Documentation

### 5.58.2.1 ERROR_TYPE

```
enum PID::ERROR_TYPE
```

An enum to distinguish between a linear and angular caluclation of PID error.

## 5.58.3 Constructor & Destructor Documentation

### 5.58.3.1 PID()

```
PID::PID (
            pid_config_t & config )
```

Create the PID object

**Parameters**

| | |
|---|---|
| *config* | the configuration data for this controller |

Create the PID object

## 5.58.4 Member Function Documentation

### 5.58.4.1 get()

```
double PID::get ( )  [override], [virtual]
```

Gets the current PID out value, from when update() was last run

**Returns**

the Out value of the controller (voltage, RPM, whatever the PID controller is controlling)

Gets the current PID out value, from when update() was last run

Implements Feedback.

### 5.58.4.2 get_error()

```
double PID::get_error ( )
```

Get the delta between the current sensor data and the target

**Returns**

the error calculated. how it is calculated depends on error_method specified in pid_config_t

Get the delta between the current sensor data and the target

### 5.58.4.3 get_sensor_val()

```
double PID::get_sensor_val ( )
```

gets the sensor value that we were last updated with

**Returns**

sensor_val

### 5.58.4.4 get_target()

```
double PID::get_target ( )
```

Get the PID's target

**Returns**

the target the PID controller is trying to achieve

### 5.58.4.5 init()

```
void PID::init (
            double start_pt,
            double set_pt,
            double start_vel = 0,
            double end_vel = 0 )  [override], [virtual]
```

Inherited from Feedback for interoperability. Update the setpoint and reset integral accumulation

start_pt can be safely ignored in this feedback controller

**Parameters**

| | |
|---|---|
| *start_pt* | commpletely ignored for PID. necessary to satisfy Feedback base |
| *set_pt* | sets the target of the PID controller |
| *start_vel* | completely ignored for PID. necessary to satisfy Feedback base |
| *end_vel* | sets the target end velocity of the PID controller |

Implements Feedback.

#### 5.58.4.6 is_on_target()

```
bool PID::is_on_target ( )  [override], [virtual]
```

Checks if the PID controller is on target.

**Returns**

true if the loop is within [deadband] for [on_target_time] seconds

Returns true if the loop is within [deadband] for [on_target_time] seconds

Implements Feedback.

#### 5.58.4.7 reset()

```
void PID::reset ( )
```

Reset the PID loop by resetting time since 0 and accumulated error.

#### 5.58.4.8 set_limits()

```
void PID::set_limits (
            double lower,
            double upper )  [override], [virtual]
```

Set the limits on the PID out. The PID out will "clip" itself to be between the limits.

**Parameters**

| | |
|---|---|
| *lower* | the lower limit. the PID controller will never command the output go below `lower` |
| *upper* | the upper limit. the PID controller will never command the output go higher than `upper` |

Set the limits on the PID out. The PID out will "clip" itself to be between the limits.

Implements Feedback.

#### 5.58.4.9 set_target()

```
void PID::set_target (
            double target )
```

Set the target for the PID loop, where the robot is trying to end up

**Parameters**

| | |
|---|---|
| *target* | the sensor reading we would like to achieve |

Set the target for the PID loop, where the robot is trying to end up

#### 5.58.4.10 update()

```
double PID::update (
            double sensor_val )  [override], [virtual]
```

Update the PID loop by taking the time difference from last update, and running the PID formula with the new sensor data

**Parameters**

| | |
|---|---|
| *sensor_val* | the distance, angle, encoder position or whatever it is we are measuring |

**Returns**

the new output. What would be returned by PID::get()

Implements Feedback.

The documentation for this class was generated from the following files:

- include/utils/controls/pid.h
- src/utils/controls/pid.cpp

## 5.59 PID::pid_config_t Struct Reference

```
#include <pid.h>
```

### Public Attributes

- double **p**

  *proportional coeffecient p ∗ error()*
- double **i**

  *integral coeffecient i ∗ integral(error)*
- double **d**

*derivitave coeffecient d ∗ derivative(error)*

- double **deadband**

  *at what threshold are we close enough to be finished*

- double **on_target_time**

  *the time in seconds that we have to be on target for to say we are officially at the target*

- ERROR_TYPE **error_method**

  *Linear or angular. wheter to do error as a simple subtraction or to wrap.*

### 5.59.1 Detailed Description

pid_config_t holds the configuration parameters for a pid controller In addtion to the constant of proportional, integral and derivative, these parameters include:

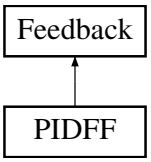
- deadband -
- on_target_time - for how long do we have to be at the target to stop As well, pid_config_t holds an error type which determines whether errors should be calculated as if the sensor position is a measure of distance or an angle

The documentation for this struct was generated from the following file:

- include/utils/controls/pid.h

## 5.60 PIDFF Class Reference

Inheritance diagram for PIDFF:




#### Public Member Functions

- **PIDFF** (PID::pid_config_t &pid_cfg, FeedForward::ff_config_t &ff_cfg)
- void init (double start_pt, double set_pt, double start_vel, double end_vel) override
- void set_target (double set_pt)
- double update (double val) override
- double update (double val, double vel_setpt, double a_setpt=0)
- double get () override
- void set_limits (double lower, double upper) override
- bool is_on_target () override

#### Public Attributes

- PID **pid**

### 5.60.1 Member Function Documentation

#### 5.60.1.1 get()

```
double PIDFF::get ( )  [override], [virtual]
```

**Returns**

the last saved result from the feedback controller

Implements Feedback.

#### 5.60.1.2 init()

```
void PIDFF::init (
            double start_pt,
            double set_pt,
            double start_vel,
            double end_vel )  [override], [virtual]
```

Initialize the feedback controller for a movement

**Parameters**

| | |
|---|---|
| *start_pt* | the current sensor value |
| *set_pt* | where the sensor value should be |
| *start_vel* | the current rate of change of the sensor value |
| *end_vel* | the desired ending rate of change of the sensor value |

Initialize the feedback controller for a movement

**Parameters**

| | |
|---|---|
| *start_pt* | the current sensor value |
| *set_pt* | where the sensor value should be |

Implements Feedback.

#### 5.60.1.3 is_on_target()

```
bool PIDFF::is_on_target ( )  [override], [virtual]
```

**Returns**

true if the feedback controller has reached it's setpoint

Implements Feedback.

#### 5.60.1.4 set_limits()

```
void PIDFF::set_limits (
            double lower,
            double upper )  [override], [virtual]
```

Clamp the upper and lower limits of the output. If both are 0, no limits should be applied.

**Parameters**

| | |
|---|---|
| *lower* | Upper limit |
| *upper* | Lower limit |

Implements Feedback.

#### 5.60.1.5 set_target()

```
void PIDFF::set_target (
            double set_pt )
```

Set the target of the PID loop

**Parameters**

| | |
|---|---|
| *set_pt* | Setpoint / target value |

#### 5.60.1.6 update() [1/2]

```
double PIDFF::update (
            double val )  [override], [virtual]
```

Iterate the feedback loop once with an updated sensor value. Only kS for feedfoward will be applied.

**Parameters**

| | |
|---|---|
| *val* | value from the sensor |

**Returns**

feedback loop result

Implements Feedback.

#### 5.60.1.7 update() [2/2]

```
double PIDFF::update (
            double val,
```

```
            double vel_setpt,
            double a_setpt = 0 )
```

Iterate the feedback loop once with an updated sensor value

**Parameters**

| | |
|---|---|
| *val* | value from the sensor |
| *vel_setpt* | Velocity for feedforward |
| *a_setpt* | Acceleration for feedfoward |

**Returns**

feedback loop result

The documentation for this class was generated from the following files:

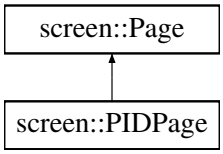
- include/utils/controls/pidff.h
- src/utils/controls/pidff.cpp

## 5.61 screen::PIDPage Class Reference

PIDPage provides a way to tune a pid controller on the screen.

`#include <screen.h>`

Inheritance diagram for screen::PIDPage:




### Public Member Functions

- PIDPage (PID &pid, std::function< void(void)> onchange=[](){})
  *Create a PIDPage.*
- **PIDPage** (PIDFF &pidff, std::function< void(void)> onchange=[](){})
- void update (bool was_pressed, int x, int y) override
- void draw (vex::brain::lcd &, bool first_draw, unsigned int frame_number) override

### 5.61.1 Detailed Description

PIDPage provides a way to tune a pid controller on the screen.

### 5.61.2 Constructor & Destructor Documentation

#### 5.61.2.1 PIDPage()

```
screen::PIDPage::PIDPage (
            PID & pid,
            std::string name,
            std::function< void(void)> onchange = [](){} )
```

Create a PIDPage.

**Parameters**

| | |
|---|---|
| *pid* | the pid controller we're changing |
| *name* | a name to recognize this pid controller if we've got multiple pid screens |
| *onchange* | a function that is called when a tuning parameter is changed. If you need to update stuff on that change register a handler here |

### 5.61.3 Member Function Documentation

#### 5.61.3.1 draw()

```
void screen::PIDPage::draw (
            vex::brain::lcd & scr,
            bool first_draw,
            unsigned int frame_number )  [override], [virtual]
```

**See also**

Page::draw

Reimplemented from screen::Page.

#### 5.61.3.2 update()

```
void screen::PIDPage::update (
            bool was_pressed,
            int x,
            int y )  [override], [virtual]
```

**See also**

Page::update

Reimplemented from screen::Page.

The documentation for this class was generated from the following files:

- include/subsystems/screen.h
- src/subsystems/screen.cpp

## 5.62 point_t Struct Reference

```
#include <geometry.h>
```

**Public Member Functions**

- double dist (const point_t other) const
- point_t operator+ (const point_t &other) const
- point_t operator- (const point_t &other) const
- point_t **operator**∗ (double s) const
- point_t **operator**/ (double s) const
- point_t **operator-** () const
- point_t **operator+** () const
- bool **operator==** (const point_t &rhs)

**Public Attributes**

- double **x**

  *the x position in space*
- double **y**

  *the y position in space*

## 5.62.1 Detailed Description

Data structure representing an X,Y coordinate

## 5.62.2 Member Function Documentation

### 5.62.2.1 dist()

```
double point_t::dist (
            const point_t other ) const  [inline]
```

dist calculates the euclidian distance between this point and another point using the pythagorean theorem

**Parameters**

| | |
|---|---|
| *other* | the point to measure the distance from |

**Returns**

the euclidian distance between this and other

### 5.62.2.2 operator+()

```
point_t point_t::operator+ (
            const point_t & other ) const  [inline]
```

Vector2D addition operation on points

**Parameters**

| | |
|---|---|
| *other* | the point to add on to this |

**Returns**

this + other (this.x + other.x, this.y + other.y)

#### 5.62.2.3 operator-()

```
point_t point_t::operator- (
            const point_t & other ) const  [inline]
```

Vector2D subtraction operation on points

**Parameters**

| | |
|---|---|
| *other* | the point_t to subtract from this |

**Returns**

this - other (this.x - other.x, this.y - other.y)

The documentation for this struct was generated from the following file:

- include/utils/geometry.h

## 5.63 pose_t Struct Reference

```
#include <geometry.h>
```

### Public Member Functions

- point_t **get_point** ()

### Public Attributes

- double **x**

  *x position in the world*
- double **y**

  *y position in the world*
- double **rot**

  *rotation in the world*

### 5.63.1 Detailed Description

Describes a single position and rotation

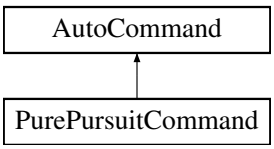
The documentation for this struct was generated from the following file:

- include/utils/geometry.h

## 5.64 PurePursuitCommand Class Reference

`#include <drive_commands.h>`

Inheritance diagram for PurePursuitCommand:




#### Public Member Functions

- PurePursuitCommand (TankDrive &drive_sys, Feedback &feedback, PurePursuit::Path path, directionType dir, double max_speed=1, double end_speed=0)
- bool run () override
- void on_timeout () override

### Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.64.1 Detailed Description

Autocommand wrapper class for pure pursuit function in the TankDrive class

### 5.64.2 Constructor & Destructor Documentation

#### 5.64.2.1 PurePursuitCommand()

```
PurePursuitCommand::PurePursuitCommand (
            TankDrive & drive_sys,
            Feedback & feedback,
            PurePursuit::Path path,
            directionType dir,
            double max_speed = 1,
            double end_speed = 0 )
```

Construct a Pure Pursuit AutoCommand

**Parameters**

| | |
|---|---|
| *path* | The list of coordinates to follow, in order |
| *dir* | Run the bot forwards or backwards |
| *feedback* | The feedback controller determining speed |
| *max_speed* | Limit the speed of the robot (for pid / pidff feedbacks) |

### 5.64.3 Member Function Documentation

#### 5.64.3.1 on_timeout()

```
void PurePursuitCommand::on_timeout ( )  [override], [virtual]
```

Reset the drive system when it times out

Reimplemented from AutoCommand.

#### 5.64.3.2 run()

```
bool PurePursuitCommand::run ( )  [override], [virtual]
```

Direct call to TankDrive::pure_pursuit

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/drive_commands.h
- src/utils/command_structure/drive_commands.cpp

## 5.65 Rect Struct Reference

**Public Member Functions**

- point_t **dimensions** () const
- point_t **center** () const
- double **width** () const
- double **height** () const
- bool **contains** (point_t p) const

#### Static Public Member Functions

- static Rect **from_min_and_size** (point_t min, point_t size)

#### Public Attributes

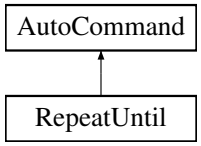
- point_t **min**
- point_t **max**

The documentation for this struct was generated from the following file:

- include/utils/geometry.h

## 5.66 RepeatUntil Class Reference

Inheritance diagram for RepeatUntil:




#### Public Member Functions

- RepeatUntil (InOrder cmds, size_t repeats)

  *RepeatUntil that runs a fixed number of times.*
- RepeatUntil (InOrder cmds, Condition *true_to_end)

  *RepeatUntil the condition.*
- bool run () override
- void on_timeout () override

### Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.66.1 Constructor & Destructor Documentation

### 5.66.1.1 RepeatUntil() [1/2]

```
RepeatUntil::RepeatUntil (
            InOrder cmds,
            size_t repeats )
```

RepeatUntil that runs a fixed number of times.

**Parameters**

| | |
|---|---|
| *cmds* | the cmds to repeat |
| *repeats* | the number of repeats to do |

#### 5.66.1.2 RepeatUntil() [2/2]

```
RepeatUntil::RepeatUntil (
            InOrder cmds,
            Condition * true_to_end )
```

RepeatUntil the condition.

**Parameters**

| | |
|---|---|
| *cmds* | the cmds to run |
| *true_to_end* | we will repeat until true_or_end.test() returns true |

### 5.66.2 Member Function Documentation

#### 5.66.2.1 on_timeout()

```
void RepeatUntil::on_timeout ( )  [override], [virtual]
```

What to do if we timeout instead of finishing. timeout is specified by the timeout seconds in the constructor

Reimplemented from AutoCommand.

#### 5.66.2.2 run()

```
bool RepeatUntil::run ( )  [override], [virtual]
```

Executes the command Overridden by child classes

**Returns**

true when the command is finished, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/auto_command.h
- src/utils/command_structure/auto_command.cpp

## 5.67 robot_specs_t Struct Reference

`#include <robot_specs.h>`

### Public Attributes

- double **robot_radius**

  *if you were to draw a circle with this radius, the robot would be entirely contained within it*
- double **odom_wheel_diam**

  *the diameter of the wheels used for*
- double **odom_gear_ratio**

  *the ratio of the odometry wheel to the encoder reading odometry data*
- double **dist_between_wheels**

  *the distance between centers of the central drive wheels*
- double **drive_correction_cutoff**

  *the distance at which to stop trying to turn towards the target. If we are less than this value, we can continue driving forward to minimize our distance but will not try to spin around to point directly at the target*
- Feedback * **drive_feedback**

  *the default feedback for autonomous driving*
- Feedback * **turn_feedback**

  *the defualt feedback for autonomous turning*
- PID::pid_config_t **correction_pid**

  *the pid controller to keep the robot driving in as straight a line as possible*

### 5.67.1 Detailed Description

Main robot characterization struct. This will be passed to all the major subsystems that require info about the robot. All distance measurements are in inches.

The documentation for this struct was generated from the following file:

- include/robot_specs.h

## 5.68 screen::ScreenData Struct Reference

The ScreenData class holds the data that will be passed to the screen thread you probably shouldnt have to use it.

### Public Member Functions

- **ScreenData** (const std::vector< Page * > &m_pages, int m_page, vex::brain::lcd &m_screen)

### Public Attributes

- std::vector< Page * > **pages**
- int **page** = 0
- vex::brain::lcd **screen**

### 5.68.1 Detailed Description

The ScreenData class holds the data that will be passed to the screen thread you probably shouldnt have to use it.

The documentation for this struct was generated from the following file:

- src/subsystems/screen.cpp

## 5.69 Serializer Class Reference

Serializes Arbitrary data to a file on the SD Card.

`#include <serializer.h>`

#### Public Member Functions

- ~**Serializer** ()

  *Save and close upon destruction (bc of vex, this doesnt always get called when the program ends. To be sure, call save_to_disk)*
- Serializer (const std::string &filename, bool flush_always=true)

  *create a Serializer*
- void save_to_disk () const

  *saves current Serializer state to disk*
- void set_int (const std::string &name, int i)

  *Setters - not saved until save_to_disk is called.*
- void set_bool (const std::string &name, bool b)

  *sets a bool by the name of name to b. If flush_always == true, this will save to the sd card*
- void set_double (const std::string &name, double d)

  *sets a double by the name of name to d. If flush_always == true, this will save to the sd card*
- void set_string (const std::string &name, std::string str)

  *sets a string by the name of name to s. If flush_always == true, this will save to the sd card*
- int int_or (const std::string &name, int otherwise)

  *gets a value stored in the serializer. If not found, sets the value to otherwise*
- bool bool_or (const std::string &name, bool otherwise)

  *gets a value stored in the serializer. If not, sets the value to otherwise*
- double double_or (const std::string &name, double otherwise)

  *gets a value stored in the serializer. If not, sets the value to otherwise*
- std::string string_or (const std::string &name, std::string otherwise)

  *gets a value stored in the serializer. If not, sets the value to otherwise*

### 5.69.1 Detailed Description

Serializes Arbitrary data to a file on the SD Card.

### 5.69.2 Constructor & Destructor Documentation

#### 5.69.2.1 Serializer()

```
Serializer::Serializer (
            const std::string & filename,
            bool flush_always = true )  [inline], [explicit]
```

create a Serializer

**Parameters**

| | |
|---|---|
| *filename* | the file to read from. If filename does not exist we will create that file |
| *flush_always* | If true, after every write flush to a file. If false, you are responsible for calling save_to_disk |

## 5.69.3 Member Function Documentation

### 5.69.3.1 bool_or()

```
bool Serializer::bool_or (
            const std::string & name,
            bool otherwise )
```

gets a value stored in the serializer. If not, sets the value to otherwise

**Parameters**

| | |
|---|---|
| *name* | name of value |
| *otherwise* | value if the name is not specified |

**Returns**

the value if found or otherwise

### 5.69.3.2 double_or()

```
double Serializer::double_or (
            const std::string & name,
            double otherwise )
```

gets a value stored in the serializer. If not, sets the value to otherwise

**Parameters**

| | |
|---|---|
| *name* | name of value |
| *otherwise* | value if the name is not specified |

**Returns**

the value if found or otherwise

### 5.69.3.3 int_or()

```
int Serializer::int_or (
            const std::string & name,
            int otherwise )
```

gets a value stored in the serializer. If not found, sets the value to otherwise

Getters Return value if it exists in the serializer

**Parameters**

| | |
|---|---|
| *name* | name of value |
| *otherwise* | value if the name is not specified |

**Returns**

the value if found or otherwise

#### 5.69.3.4 save_to_disk()

```
void Serializer::save_to_disk ( ) const
```

saves current Serializer state to disk

forms data bytes then saves to filename this was openned with

#### 5.69.3.5 set_bool()

```
void Serializer::set_bool (
            const std::string & name,
            bool b )
```

sets a bool by the name of name to b. If flush_always == true, this will save to the sd card

**Parameters**

| | |
|---|---|
| *name* | name of bool |
| *b* | value of bool |

#### 5.69.3.6 set_double()

```
void Serializer::set_double (
            const std::string & name,
            double d )
```

sets a double by the name of name to d. If flush_always == true, this will save to the sd card

**Parameters**

| | |
|---|---|
| *name* | name of double |
| *d* | value of double |

#### 5.69.3.7 set_int()

```
void Serializer::set_int (
```

```
            const std::string & name,
            int i )
```

Setters - not saved until save_to_disk is called.

sets an integer by the name of name to i. If flush_always == true, this will save to the sd card

**Parameters**

| | |
|---|---|
| *name* | name of integer |
| *i* | value of integer |

#### 5.69.3.8 set_string()

```
void Serializer::set_string (
            const std::string & name,
            std::string str )
```

sets a string by the name of name to s. If flush_always == true, this will save to the sd card

**Parameters**

| | |
|---|---|
| *name* | name of string |
| *i* | value of string |

#### 5.69.3.9 string_or()

```
std::string Serializer::string_or (
            const std::string & name,
            std::string otherwise )
```

gets a value stored in the serializer. If not, sets the value to otherwise

**Parameters**

| | |
|---|---|
| *name* | name of value |
| *otherwise* | value if the name is not specified |

**Returns**

the value if found or otherwise

The documentation for this class was generated from the following files:

- include/utils/serializer.h
- src/utils/serializer.cpp

# 5.70 screen::SliderWidget Class Reference

Widget that updates a double value. Updates by reference so watch out for race conditions cuz the screen stuff lives on another thread.

`#include <screen.h>`

### Public Member Functions

- SliderWidget (double &val, double low, double high, Rect rect, std::string name)

  *Creates a slider widget.*
- bool update (bool was_pressed, int x, int y)

  *responds to user input*
- void **draw** (vex::brain::lcd &, bool first_draw, unsigned int frame_number)

  *Page::draws the slide to the screen*

## 5.70.1 Detailed Description

Widget that updates a double value. Updates by reference so watch out for race conditions cuz the screen stuff lives on another thread.

## 5.70.2 Constructor & Destructor Documentation

### 5.70.2.1 SliderWidget()

```
screen::SliderWidget::SliderWidget (
            double & val,
            double low,
            double high,
            Rect rect,
            std::string name )  [inline]
```

Creates a slider widget.

**Parameters**

| | |
|---|---|
| *val* | reference to the value to modify |
| *low* | minimum value to go to |
| *high* | maximum value to go to |
| *rect* | rect to draw it |
| *name* | name of the value |

## 5.70.3 Member Function Documentation

### 5.70.3.1 update()

```
bool screen::SliderWidget::update (
```

```
bool was_pressed,
int x,
int y )
```

responds to user input

**Parameters**

| | |
|---|---|
| *was_pressed* | if the screen is pressed |
| *x* | x position if the screen was pressed |
| *y* | y position if the screen was pressed |

**Returns**

true if the value updated

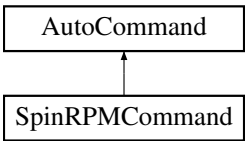
The documentation for this class was generated from the following files:

- include/subsystems/screen.h
- src/subsystems/screen.cpp

## 5.71 SpinRPMCommand Class Reference

`#include <flywheel_commands.h>`

Inheritance diagram for SpinRPMCommand:




### Public Member Functions

- SpinRPMCommand (Flywheel &flywheel, int rpm)
- bool run () override

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

## Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.71.1 Detailed Description

File: flywheel_commands.h Desc: [insert meaningful desc] AutoCommand wrapper class for the spin_rpm function in the Flywheel class

### 5.71.2 Constructor & Destructor Documentation

#### 5.71.2.1 SpinRPMCommand()

```
SpinRPMCommand::SpinRPMCommand (
            Flywheel & flywheel,
            int rpm )
```

Construct a SpinRPM Command

**Parameters**

| | |
|---|---|
| *flywheel* | the flywheel sys to command |
| *rpm* | the rpm that we should spin at |

File: flywheel_commands.cpp Desc: [insert meaningful desc]

### 5.71.3 Member Function Documentation

#### 5.71.3.1 run()

```
bool SpinRPMCommand::run ( )  [override], [virtual]
```

Run spin_manual Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/flywheel_commands.h
- src/utils/command_structure/flywheel_commands.cpp

## 5.72 PurePursuit::spline Struct Reference

`#include <pure_pursuit.h>`

### Public Member Functions

- double **getY** (double x)

### Public Attributes

- double **a**
- double **b**
- double **c**
- double **d**
- double **x_start**
- double **x_end**

### 5.72.1 Detailed Description

Represents a piece of a cubic spline with s(x) = a(x-xi)^3 + b(x-xi)^2 + c(x-xi) + d The x_start and x_end shows where the equation is valid.

The documentation for this struct was generated from the following file:

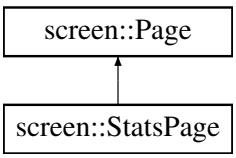
- include/utils/pure_pursuit.h

## 5.73 screen::StatsPage Class Reference

Draws motor stats and battery stats to the screen.

`#include <screen.h>`

Inheritance diagram for screen::StatsPage:




### Public Member Functions

- StatsPage (std::map< std::string, vex::motor & > motors)

  *Creates a stats page.*
- void update (bool was_pressed, int x, int y) override
- void draw (vex::brain::lcd &, bool first_draw, unsigned int frame_number) override

### 5.73.1 Detailed Description

Draws motor stats and battery stats to the screen.

### 5.73.2 Constructor & Destructor Documentation

#### 5.73.2.1 StatsPage()

```
screen::StatsPage::StatsPage (
            std::map< std::string, vex::motor & > motors )
```

Creates a stats page.

**Parameters**

| | |
|---|---|
| *motors* | a map of string to motor that we want to draw on this page |

### 5.73.3 Member Function Documentation

#### 5.73.3.1 draw()

```
void screen::StatsPage::draw (
            vex::brain::lcd & scr,
            bool first_draw,
            unsigned int frame_number )  [override], [virtual]
```

**See also**

Page::draw

Reimplemented from screen::Page.

#### 5.73.3.2 update()

```
void screen::StatsPage::update (
            bool was_pressed,
            int x,
            int y )  [override], [virtual]
```

**See also**

Page::update

Reimplemented from screen::Page.

The documentation for this class was generated from the following files:

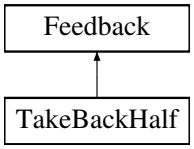
- include/subsystems/screen.h
- src/subsystems/screen.cpp

## 5.74 TakeBackHalf Class Reference

A velocity controller.

`#include <take_back_half.h>`

Inheritance diagram for TakeBackHalf:




### Public Member Functions

- **TakeBackHalf** (double TBH_gain, double first_cross_split, double on_target_threshold)
- void init (double start_pt, double set_pt, double, double)
- double update (double val) override
- double get () override
- void set_limits (double lower, double upper) override
- bool is_on_target () override

### Public Attributes

- double **TBH_gain**

  *tuned parameter*
- double **first_cross_split**

### 5.74.1 Detailed Description

A velocity controller.

**Warning**

If you try to use this as a position controller, it will fail.

### 5.74.2 Member Function Documentation

#### 5.74.2.1 get()

```
double TakeBackHalf::get ( )  [override], [virtual]
```

**Returns**

the last saved result from the feedback controller

Implements Feedback.

#### 5.74.2.2 init()

```
void TakeBackHalf::init (
            double start_pt,
            double set_pt,
            double ,
            double  )  [virtual]
```

Initialize the feedback controller for a movement

**Parameters**

| | |
|---|---|
| *start_pt* | the current sensor value |
| *set_pt* | where the sensor value should be |
| *start_vel* | Movement starting velocity (IGNORED) |
| *end_vel* | Movement ending velocity (IGNORED) |

Implements Feedback.

#### 5.74.2.3 is_on_target()

```
bool TakeBackHalf::is_on_target ( )  [override], [virtual]
```

**Returns**

true if the feedback controller has reached it's setpoint

Implements Feedback.

#### 5.74.2.4 set_limits()

```
void TakeBackHalf::set_limits (
            double lower,
            double upper )  [override], [virtual]
```

Clamp the upper and lower limits of the output. If both are 0, no limits should be applied.

**Parameters**

| | |
|---|---|
| *lower* | Upper limit |
| *upper* | Lower limit |

Implements Feedback.

#### 5.74.2.5 update()

```
double TakeBackHalf::update (
            double val )  [override], [virtual]
```

Iterate the feedback loop once with an updated sensor value

**Parameters**

| | |
|---|---|
| *val* | value from the sensor |

**Returns**

feedback loop result

Implements Feedback.

The documentation for this class was generated from the following files:

- include/utils/controls/take_back_half.h
- src/utils/controls/take_back_half.cpp

## 5.75 TankDrive Class Reference

`#include <tank_drive.h>`

### Public Member Functions

- TankDrive (motor_group &left_motors, motor_group &right_motors, robot_specs_t &config, OdometryBase *odom=NULL)
- AutoCommand * **DriveToPointCmd** (point_t pt, vex::directionType dir=vex::forward, double max_speed=1.0, double end_speed=0.0)
- AutoCommand * **DriveToPointCmd** (Feedback &fb, point_t pt, vex::directionType dir=vex::forward, double max_speed=1.0, double end_speed=0.0)
- AutoCommand * **DriveForwardCmd** (double dist, vex::directionType dir=vex::forward, double max_speed=1.0, double end_speed=0.0)
- AutoCommand * **DriveForwardCmd** (Feedback &fb, double dist, vex::directionType dir=vex::forward, double max_speed=1.0, double end_speed=0.0)
- AutoCommand * **TurnToHeadingCmd** (double heading, double max_speed=1.0, double end_speed=0.0)
- AutoCommand * **TurnToHeadingCmd** (Feedback &fb, double heading, double max_speed=1.0, double end_speed=0.0)
- AutoCommand * **TurnDegreesCmd** (double degrees, double max_speed=1.0, double start_speed=0.0)
- AutoCommand * **TurnDegreesCmd** (Feedback &fb, double degrees, double max_speed=1.0, double end_speed=0.0)
- AutoCommand * **PurePursuitCmd** (PurePursuit::Path path, directionType dir, double max_speed=1, double end_speed=0)
- AutoCommand * **PurePursuitCmd** (Feedback &feedback, PurePursuit::Path path, directionType dir, double max_speed=1, double end_speed=0)
- void stop ()
- void drive_tank (double left, double right, int power=1)
- void drive_arcade (double forward_back, double left_right, int power=1)
- bool drive_forward (double inches, directionType dir, Feedback &feedback, double max_speed=1, double end_speed=0)
- bool drive_forward (double inches, directionType dir, double max_speed=1, double end_speed=0)
- bool turn_degrees (double degrees, Feedback &feedback, double max_speed=1, double end_speed=0)
- bool turn_degrees (double degrees, double max_speed=1, double end_speed=0)
- bool drive_to_point (double x, double y, vex::directionType dir, Feedback &feedback, double max_speed=1, double end_speed=0)
- bool drive_to_point (double x, double y, vex::directionType dir, double max_speed=1, double end_speed=0)
- bool turn_to_heading (double heading_deg, Feedback &feedback, double max_speed=1, double end_speed=0)
- bool turn_to_heading (double heading_deg, double max_speed=1, double end_speed=0)
- void reset_auto ()
- bool pure_pursuit (PurePursuit::Path path, directionType dir, Feedback &feedback, double max_speed=1, double end_speed=0)
- bool pure_pursuit (PurePursuit::Path path, directionType dir, double max_speed=1, double end_speed=0)

### Static Public Member Functions

- static double modify_inputs (double input, int power=2)

## 5.75.1 Detailed Description

TankDrive is a class to run a tank drive system. A tank drive system, sometimes called differential drive, has a motor (or group of synchronized motors) on the left and right side

## 5.75.2 Constructor & Destructor Documentation

### 5.75.2.1 TankDrive()

```
TankDrive::TankDrive (
            motor_group & left_motors,
            motor_group & right_motors,
            robot_specs_t & config,
            OdometryBase * odom = NULL )
```

Create the TankDrive object

**Parameters**

| | |
|---|---|
| *left_motors* | left side drive motors |
| *right_motors* | right side drive motors |
| *config* | the configuration specification defining physical dimensions about the robot. See robot_specs_t for more info |
| *odom* | an odometry system to track position and rotation. this is necessary to execute autonomous paths |

## 5.75.3 Member Function Documentation

### 5.75.3.1 drive_arcade()

```
void TankDrive::drive_arcade (
            double forward_back,
            double left_right,
            int power = 1 )
```

Drive the robot using arcade style controls. forward_back controls the linear motion, left_right controls the turning.

forward_back and left_right are in "percent": -1.0 -> 1.0

**Parameters**

| | |
|---|---|
| *forward_back* | the percent to move forward or backward |
| *left_right* | the percent to turn left or right |
| *power* | modifies the input velocities left^power, right^power |

Drive the robot using arcade style controls. forward_back controls the linear motion, left_right controls the turning.

left_motors and right_motors are in "percent": -1.0 -> 1.0

#### 5.75.3.2 drive_forward() [1/2]

```
bool TankDrive::drive_forward (
            double inches,
            directionType dir,
            double max_speed = 1,
            double end_speed = 0 )
```

Autonomously drive the robot forward a certain distance

**Parameters**

| | |
|---|---|
| *inches* | degrees by which we will turn relative to the robot (+) turns ccw, (-) turns cw |
| *dir* | the direction we want to travel forward and backward |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

Autonomously drive the robot forward a certain distance

**Parameters**

| | |
|---|---|
| *inches* | degrees by which we will turn relative to the robot (+) turns ccw, (-) turns cw |
| *dir* | the direction we want to travel forward and backward |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

true if we have finished driving to our point

#### 5.75.3.3 drive_forward() [2/2]

```
bool TankDrive::drive_forward (
            double inches,
            directionType dir,
            Feedback & feedback,
            double max_speed = 1,
            double end_speed = 0 )
```

Use odometry to drive forward a certain distance using a custom feedback controller

Returns whether or not the robot has reached it's destination.

**Parameters**

| | |
|---|---|
| *inches* | the distance to drive forward |

**Parameters**

| | |
|---|---|
| *dir* | the direction we want to travel forward and backward |
| *feedback* | the custom feedback controller we will use to travel. controls the rate at which we accelerate and drive. |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

true when we have reached our target distance

Use odometry to drive forward a certain distance using a custom feedback controller

Returns whether or not the robot has reached it's destination.

**Parameters**

| | |
|---|---|
| *inches* | the distance to drive forward |
| *dir* | the direction we want to travel forward and backward |
| *feedback* | the custom feedback controller we will use to travel. controls the rate at which we accelerate and drive. |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

#### 5.75.3.4 drive_tank()

```
void TankDrive::drive_tank (
            double left,
            double right,
            int power = 1 )
```

Drive the robot using differential style controls. left_motors controls the left motors, right_motors controls the right motors.

left_motors and right_motors are in "percent": -1.0 -> 1.0

**Parameters**

| | |
|---|---|
| *left* | the percent to run the left motors |
| *right* | the percent to run the right motors |
| *power* | modifies the input velocities left^power, right^power |
| *isdriver* | default false. if true uses motor percentage. if false uses plain percentage of maximum voltage |

Drive the robot using differential style controls. left_motors controls the left motors, right_motors controls the right motors.

left_motors and right_motors are in "percent": -1.0 -> 1.0

#### 5.75.3.5 drive_to_point() [1/2]

```
bool TankDrive::drive_to_point (
            double x,
            double y,
            vex::directionType dir,
            double max_speed = 1,
            double end_speed = 0 )
```

Use odometry to automatically drive the robot to a point on the field. X and Y is the final point we want the robot. Here we use the default feedback controller from the drive_sys

Returns whether or not the robot has reached it's destination.

**Parameters**

| | |
|---|---|
| *x* | the x position of the target |
| *y* | the y position of the target |
| *dir* | the direction we want to travel forward and backward |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

Use odometry to automatically drive the robot to a point on the field. X and Y is the final point we want the robot. Here we use the default feedback controller from the drive_sys

Returns whether or not the robot has reached it's destination.

**Parameters**

| | |
|---|---|
| *x* | the x position of the target |
| *y* | the y position of the target |
| *dir* | the direction we want to travel forward and backward |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

true if we have reached our target point

#### 5.75.3.6 drive_to_point() [2/2]

```
bool TankDrive::drive_to_point (
            double x,
            double y,
            vex::directionType dir,
            Feedback & feedback,
            double max_speed = 1,
            double end_speed = 0 )
```

Use odometry to automatically drive the robot to a point on the field. X and Y is the final point we want the robot.

Returns whether or not the robot has reached it's destination.

**Parameters**

| | |
|---|---|
| *x* | the x position of the target |
| *y* | the y position of the target |
| *dir* | the direction we want to travel forward and backward |
| *feedback* | the feedback controller we will use to travel. controls the rate at which we accelerate and drive. |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

Use odometry to automatically drive the robot to a point on the field. X and Y is the final point we want the robot.

Returns whether or not the robot has reached it's destination.

**Parameters**

| | |
|---|---|
| *x* | the x position of the target |
| *y* | the y position of the target |
| *dir* | the direction we want to travel forward and backward |
| *feedback* | the feedback controller we will use to travel. controls the rate at which we accelerate and drive. |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

true if we have reached our target point

#### 5.75.3.7 modify_inputs()

```
double TankDrive::modify_inputs (
            double input,
            int power = 2 )  [static]
```

Create a curve for the inputs, so that drivers have more control at lower speeds. Curves are exponential, with the default being squaring the inputs.

**Parameters**

| | |
|---|---|
| *input* | the input before modification |
| *power* | the power to raise input to |

**Returns**

input ^ power (accounts for negative inputs and odd numbered powers)

Modify the inputs from the controller by squaring / cubing, etc Allows for better control of the robot at slower speeds

**Parameters**

| | |
|---|---|
| *input* | the input signal -1 -> 1 |
| *power* | the power to raise the signal to |

**Returns**

input^power accounting for any sign issues that would arise with this naive solution

#### 5.75.3.8 pure_pursuit() [1/2]

```
bool TankDrive::pure_pursuit (
            PurePursuit::Path path,
            directionType dir,
            double max_speed = 1,
            double end_speed = 0 )
```

Drive the robot autonomously using a pure-pursuit algorithm - Input path with a set of waypoints - the robot will attempt to follow the points while cutting corners (radius) to save time (compared to stop / turn / start)

Use the default drive feedback

**Parameters**

| | |
|---|---|
| *path* | The list of coordinates to follow, in order |
| *dir* | Run the bot forwards or backwards |
| *max_speed* | Limit the speed of the robot (for pid / pidff feedbacks) |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

True when the path is complete

Drive the robot autonomously using a pure-pursuit algorithm - Input path with a set of waypoints - the robot will attempt to follow the points while cutting corners (radius) to save time (compared to stop / turn / start)

Use the default drive feedback

**Parameters**

| | |
|---|---|
| *path* | The list of coordinates to follow, in order |
| *dir* | Run the bot forwards or backwards |
| *max_speed* | Limit the speed of the robot (for pid / pidff feedbacks) |

**Returns**

True when the path is complete

#### 5.75.3.9 pure_pursuit() [2/2]

```
bool TankDrive::pure_pursuit (
            PurePursuit::Path path,
            directionType dir,
            Feedback & feedback,
```

```
double max_speed = 1,
double end_speed = 0 )
```

Drive the robot autonomously using a pure-pursuit algorithm - Input path with a set of waypoints - the robot will attempt to follow the points while cutting corners (radius) to save time (compared to stop / turn / start)

**Parameters**

| | |
|---|---|
| *path* | The list of coordinates to follow, in order |
| *dir* | Run the bot forwards or backwards |
| *feedback* | The feedback controller determining speed |
| *max_speed* | Limit the speed of the robot (for pid / pidff feedbacks) |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

True when the path is complete

Drive the robot autonomously using a pure-pursuit algorithm - Input path with a set of waypoints - the robot will attempt to follow the points while cutting corners (radius) to save time (compared to stop / turn / start)

**Parameters**

| | |
|---|---|
| *path* | The list of coordinates to follow, in order |
| *dir* | Run the bot forwards or backwards |
| *feedback* | The feedback controller determining speed |
| *max_speed* | Limit the speed of the robot (for pid / pidff feedbacks) |

**Returns**

True when the path is complete

#### 5.75.3.10 reset_auto()

```
void TankDrive::reset_auto ( )
```

Reset the initialization for autonomous drive functions

#### 5.75.3.11 stop()

```
void TankDrive::stop ( )
```

Stops rotation of all the motors using their "brake mode"

#### 5.75.3.12 turn_degrees() [1/2]

```
bool TankDrive::turn_degrees (
            double degrees,
            double max_speed = 1,
            double end_speed = 0 )
```

Autonomously turn the robot X degrees to counterclockwise (negative for clockwise), with a maximum motor speed of percent_speed (-1.0 -> 1.0)

Uses the defualt turning feedback of the drive system.

**Parameters**

| | |
|---|---|
| *degrees* | degrees by which we will turn relative to the robot (+) turns ccw, (-) turns cw |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

Autonomously turn the robot X degrees to counterclockwise (negative for clockwise), with a maximum motor speed of percent_speed (-1.0 -> 1.0)

Uses the defualt turning feedback of the drive system.

**Parameters**

| | |
|---|---|
| *degrees* | degrees by which we will turn relative to the robot (+) turns ccw, (-) turns cw |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

true if we turned te target number of degrees

#### 5.75.3.13 turn_degrees() [2/2]

```
bool TankDrive::turn_degrees (
            double degrees,
            Feedback & feedback,
            double max_speed = 1,
            double end_speed = 0 )
```

Autonomously turn the robot X degrees counterclockwise (negative for clockwise), with a maximum motor speed of percent_speed (-1.0 -> 1.0)

Uses PID + Feedforward for it's control.

**Parameters**

| | |
|---|---|
| *degrees* | degrees by which we will turn relative to the robot (+) turns ccw, (-) turns cw |
| *feedback* | the feedback controller we will use to travel. controls the rate at which we accelerate and drive. |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |

Autonomously turn the robot X degrees to counterclockwise (negative for clockwise), with a maximum motor speed of percent_speed (-1.0 -> 1.0)

Uses the specified feedback for it's control.

**Parameters**

| | |
|---|---|
| *degrees* | degrees by which we will turn relative to the robot (+) turns ccw, (-) turns cw |
| *feedback* | the feedback controller we will use to travel. controls the rate at which we accelerate and drive. |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

true if we have turned our target number of degrees

#### 5.75.3.14 turn_to_heading() [1/2]

```
bool TankDrive::turn_to_heading (
            double heading_deg,
            double max_speed = 1,
            double end_speed = 0 )
```

Turn the robot in place to an exact heading relative to the field. 0 is forward. Uses the defualt turn feedback of the drive system

**Parameters**

| | |
|---|---|
| *heading_deg* | the heading to which we will turn |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

Turn the robot in place to an exact heading relative to the field. 0 is forward. Uses the defualt turn feedback of the drive system

**Parameters**

| | |
|---|---|
| *heading_deg* | the heading to which we will turn |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

true if we have reached our target heading

#### 5.75.3.15 turn_to_heading() [2/2]

```
bool TankDrive::turn_to_heading (
            double heading_deg,
            Feedback & feedback,
            double max_speed = 1,
            double end_speed = 0 )
```

Turn the robot in place to an exact heading relative to the field. 0 is forward.

**Parameters**

| | |
|---|---|
| *heading_deg* | the heading to which we will turn |
| *feedback* | the feedback controller we will use to travel. controls the rate at which we accelerate and drive. |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

Turn the robot in place to an exact heading relative to the field. 0 is forward.

**Parameters**

| | |
|---|---|
| *heading_deg* | the heading to which we will turn |
| *feedback* | the feedback controller we will use to travel. controls the rate at which we accelerate and drive. |
| *max_speed* | the maximum percentage of robot speed at which the robot will travel. 1 = full power |
| *end_speed* | the movement profile will attempt to reach this velocity by its completion |

**Returns**

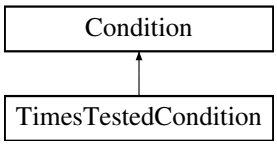
true if we have reached our target heading

The documentation for this class was generated from the following files:

- include/subsystems/tank_drive.h
- src/subsystems/tank_drive.cpp

## 5.76 TimesTestedCondition Class Reference

Inheritance diagram for TimesTestedCondition:




### Public Member Functions

- **TimesTestedCondition** (size_t N)
- bool test () override

### Public Member Functions inherited from Condition

- Condition * **Or** (Condition *b)
- Condition * **And** (Condition *b)

### 5.76.1 Member Function Documentation

#### 5.76.1.1 test()

```
bool TimesTestedCondition::test ( )  [inline], [override], [virtual]
```

Implements Condition.

The documentation for this class was generated from the following file:

- include/utils/command_structure/auto_command.h

## 5.77 trapezoid_profile_segment_t Struct Reference

`#include <trapezoid_profile.h>`

### Public Attributes

- double **pos_after**

  *1d position after this segment concludes*
- double **vel_after**

  *1d velocity after this segment concludes*
- double **accel**

  *1d acceleration during the segment*
- double **duration**

  *duration of the segment*

### 5.77.1 Detailed Description

trapezoid_profile_segment_t is a description of one constant acceleration segment of a trapezoid motion profile

The documentation for this struct was generated from the following file:

- include/utils/controls/trapezoid_profile.h

## 5.78 TrapezoidProfile Class Reference

`#include <trapezoid_profile.h>`

### Public Member Functions

- TrapezoidProfile (double max_v, double accel)

  *Construct a new Trapezoid Profile object.*
- motion_t calculate (double time_s, double pos_s)

  *Run the trapezoidal profile based on the time and distance that's elapsed.*
- motion_t calculate_time_based (double time_s)

  *Run the trapezoidal profile based on the time that's elapsed.*
- void set_endpts (double start, double end)

  *set_endpts defines a start and end position*
- void set_vel_endpts (double start, double end)

  *set start and end velocities*
- void set_accel (double accel)

  *set_accel sets the acceleration this profile will use (the left and right legs of the trapezoid)*
- void set_max_v (double max_v)

  *sets the maximum velocity for the profile (the height of the top of the trapezoid)*
- double get_movement_time ()

  *uses the kinematic equations to and specified accel and max_v to figure out how long moving along the profile would take*

### 5.78.1 Detailed Description

Trapezoid Profile

This is a motion profile defined by:

- maximum acceleration
- maximum velocity
- start position and velocity
- end position and velocity

Using this information, a parametric function is generated, with a period of acceleration, constant velocity, and deceleration. The velocity graph usually looks like a trapezoid, giving it its name.

If the maximum velocity is set high enough, this will become a S-curve profile, with only acceleration and deceleration.

If the initial velocity is in the wrong direction, the profile will first come to a stop, then continue a normal trapezoid profile.

If the initial velocity is higher than the maximum velocity, the profile will first try to achieve the maximum velocity.

If the end velocity is not achievable, the profile will try to get as close as possible. The end velocity must be in the direction of the end point.

This class is designed for use in properly modelling the motion of the robots to create a feedfoward and target for PID. Acceleration and Maximum velocity should be measured on the robot and tuned down slightly to account for battery drop.

Here are the equations graphed for ease of understanding: https://www.desmos.com/calculator/rkm3ivu1yk

**Author**

Ryan McGee

**Date**

7/12/2022

### 5.78.2 Constructor & Destructor Documentation

#### 5.78.2.1 TrapezoidProfile()

```
TrapezoidProfile::TrapezoidProfile (
            double max_v,
            double accel )
```

Construct a new Trapezoid Profile object.

**Parameters**

| | |
|---|---|
| *max_v* | Maximum velocity the robot can run at |
| *accel* | Maximum acceleration of the robot |

### 5.78.3 Member Function Documentation

#### 5.78.3.1 calculate()

```
motion_t TrapezoidProfile::calculate (
            double time_s,
            double pos_s )
```

Run the trapezoidal profile based on the time and distance that's elapsed.

**Parameters**

| | |
|---|---|
| *time_s* | Time since start of movement |
| *pos_s* | The current position |

**Returns**

motion_t Position, velocity and acceleration

#### 5.78.3.2 calculate_time_based()

```
motion_t TrapezoidProfile::calculate_time_based (
            double time_s )
```

Run the trapezoidal profile based on the time that's elapsed.

**Parameters**

| | |
|---|---|
| *time_s* | Time since start of movement |

**Returns**

motion_t Position, velocity and acceleration

#### 5.78.3.3 get_movement_time()

```
double TrapezoidProfile::get_movement_time ( )
```

uses the kinematic equations to and specified accel and max_v to figure out how long moving along the profile would take

**Returns**

the time the path will take to travel

#### 5.78.3.4 set_accel()

```
void TrapezoidProfile::set_accel (
            double accel )
```

set_accel sets the acceleration this profile will use (the left and right legs of the trapezoid)

**Parameters**

| | |
|---|---|
| *accel* | the acceleration amount to use |

#### 5.78.3.5 set_endpts()

```
void TrapezoidProfile::set_endpts (
            double start,
            double end )
```

set_endpts defines a start and end position

**Parameters**

| | |
|---|---|
| *start* | the starting position of the path |
| *end* | the ending position of the path |

#### 5.78.3.6 set_max_v()

```
void TrapezoidProfile::set_max_v (
            double max_v )
```

sets the maximum velocity for the profile (the height of the top of the trapezoid)

**Parameters**

| | |
|---|---|
| *max_v* | the maximum velocity the robot can travel at |

#### 5.78.3.7 set_vel_endpts()

```
void TrapezoidProfile::set_vel_endpts (
            double start,
            double end )
```

set start and end velocities

**Parameters**

| | |
|---|---|
| *start* | the starting velocity of the path |
| *end* | the ending velocity of the path |

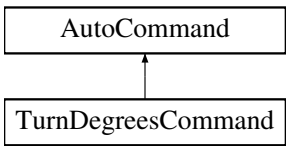
The documentation for this class was generated from the following files:

- include/utils/controls/trapezoid_profile.h
- src/utils/trapezoid_profile.cpp

## 5.79 TurnDegreesCommand Class Reference

`#include <drive_commands.h>`

Inheritance diagram for TurnDegreesCommand:




### Public Member Functions

- TurnDegreesCommand (TankDrive &drive_sys, Feedback &feedback, double degrees, double max_speed=1, double end_speed=0)
- bool run () override
- void on_timeout () override

### Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.79.1 Detailed Description

AutoCommand wrapper class for the turn_degrees function in the TankDrive class

### 5.79.2 Constructor & Destructor Documentation

#### 5.79.2.1 TurnDegreesCommand()

```
TurnDegreesCommand::TurnDegreesCommand (
            TankDrive & drive_sys,
            Feedback & feedback,
            double degrees,
            double max_speed = 1,
            double end_speed = 0 )
```

Construct a TurnDegreesCommand Command

**Parameters**

| | |
|---|---|
| *drive_sys* | the drive system we are commanding |
| *feedback* | the feedback controller we are using to execute the turn |
| *degrees* | how many degrees to rotate |
| *max_speed* | 0 -> 1 percentage of the drive systems speed to drive at |

### 5.79.3 Member Function Documentation

#### 5.79.3.1 on_timeout()

```
void TurnDegreesCommand::on_timeout ( )  [override], [virtual]
```

Cleans up drive system if we time out before finishing

reset the drive system if we timeout

Reimplemented from AutoCommand.

#### 5.79.3.2 run()

```
bool TurnDegreesCommand::run ( )  [override], [virtual]
```

Run turn_degrees Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

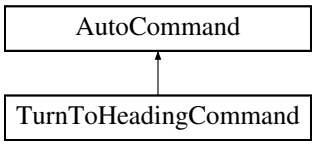
The documentation for this class was generated from the following files:

- include/utils/command_structure/drive_commands.h
- src/utils/command_structure/drive_commands.cpp

## 5.80 TurnToHeadingCommand Class Reference

`#include <drive_commands.h>`

Inheritance diagram for TurnToHeadingCommand:




#### Public Member Functions

- TurnToHeadingCommand (TankDrive &drive_sys, Feedback &feedback, double heading_deg, double speed=1, double end_speed=0)
- bool run () override
- void on_timeout () override

### Public Member Functions inherited from AutoCommand

- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

### 5.80.1 Detailed Description

AutoCommand wrapper class for the turn_to_heading() function in the TankDrive class

### 5.80.2 Constructor & Destructor Documentation

#### 5.80.2.1 TurnToHeadingCommand()

```
TurnToHeadingCommand::TurnToHeadingCommand (
            TankDrive & drive_sys,
            Feedback & feedback,
            double heading_deg,
            double max_speed = 1,
            double end_speed = 0 )
```

Construct a TurnToHeadingCommand Command

**Parameters**

| | |
|---|---|
| *drive_sys* | the drive system we are commanding |
| *feedback* | the feedback controller we are using to execute the drive |
| *heading_deg* | the heading to turn to in degrees |
| *max_speed* | 0 -> 1 percentage of the drive systems speed to drive at |

### 5.80.3 Member Function Documentation

#### 5.80.3.1 on_timeout()

```
void TurnToHeadingCommand::on_timeout ( )  [override], [virtual]
```

Cleans up drive system if we time out before finishing

reset the drive system if we don't hit our target

Reimplemented from AutoCommand.

#### 5.80.3.2 run()

```
bool TurnToHeadingCommand::run ( )  [override], [virtual]
```

Run turn_to_heading Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/drive_commands.h
- src/utils/command_structure/drive_commands.cpp

## 5.81 Vector2D Class Reference

```
#include <vector2d.h>
```

**Public Member Functions**

- Vector2D (double dir, double mag)
- Vector2D (point_t p)
- double get_dir () const
- double get_mag () const
- double get_x () const
- double get_y () const
- Vector2D normalize ()
- point_t point ()
- Vector2D operator∗ (const double &x)
- Vector2D operator+ (const Vector2D &other)
- Vector2D operator- (const Vector2D &other)

### 5.81.1 Detailed Description

Vector2D is an x,y pair Used to represent 2D locations on the field. It can also be treated as a direction and magnitude

### 5.81.2 Constructor & Destructor Documentation

#### 5.81.2.1 Vector2D() [1/2]

```
Vector2D::Vector2D (
            double dir,
            double mag )
```

Construct a vector object.

**Parameters**

| | |
|---|---|
| *dir* | Direction, in radians. 'foward' is 0, clockwise positive when viewed from the top. |
| *mag* | Magnitude. |

#### 5.81.2.2 Vector2D() [2/2]

```
Vector2D::Vector2D (
            point_t p )
```

Construct a vector object from a cartesian point.

**Parameters**

| | |
|---|---|
| *p* | point_t.x , point_t.y |

## 5.81.3 Member Function Documentation

### 5.81.3.1 get_dir()

```
double Vector2D::get_dir ( ) const
```

Get the direction of the vector, in radians. '0' is forward, clockwise positive when viewed from the top.

Use r2d() to convert.

**Returns**

the direction of the vetctor in radians

Get the direction of the vector, in radians. '0' is forward, clockwise positive when viewed from the top.

Use r2d() to convert.

### 5.81.3.2 get_mag()

```
double Vector2D::get_mag ( ) const
```

**Returns**

the magnitude of the vector

Get the magnitude of the vector

### 5.81.3.3 get_x()

```
double Vector2D::get_x ( ) const
```

**Returns**

the X component of the vector; positive to the right.

Get the X component of the vector; positive to the right.

### 5.81.3.4 get_y()

```
double Vector2D::get_y ( ) const
```

**Returns**

the Y component of the vector, positive forward.

Get the Y component of the vector, positive forward.

#### 5.81.3.5 normalize()

```
Vector2D Vector2D::normalize ( )
```

Changes the magnitude of the vector to 1

**Returns**

the normalized vector

Changes the magnetude of the vector to 1

#### 5.81.3.6 operator∗()

```
Vector2D Vector2D::operator* (
            const double & x )
```

Scales a Vector2D by a scalar with the ∗ operator

**Parameters**

| | |
|---|---|
| *x* | the value to scale the vector by |

**Returns**

the this Vector2D scaled by x

#### 5.81.3.7 operator+()

```
Vector2D Vector2D::operator+ (
            const Vector2D & other )
```

Add the components of two vectors together Vector2D + Vector2D = (this.x + other.x, this.y + other.y)

**Parameters**

| | |
|---|---|
| *other* | the vector to add to this |

**Returns**

the sum of the vectors

#### 5.81.3.8 operator-()

```
Vector2D Vector2D::operator- (
            const Vector2D & other )
```

Subtract the components of two vectors together Vector2D - Vector2D = (this.x - other.x, this.y - other.y)

**Parameters**

| | |
|---|---|
| *other* | the vector to subtract from this |

**Returns**

the difference of the vectors

#### 5.81.3.9 point()

```
point_t Vector2D::point ( )
```

Returns a point from the vector

**Returns**

the point represented by the vector

Convert a direction and magnitude representation to an x, y representation

**Returns**

the x, y representation of the vector

The documentation for this class was generated from the following files:

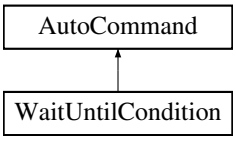
- include/utils/vector2d.h
- src/utils/vector2d.cpp

## 5.82 WaitUntilCondition Class Reference

Waits until the condition is true.

```
#include <auto_command.h>
```

Inheritance diagram for WaitUntilCondition:




### Public Member Functions

- **WaitUntilCondition** (Condition *cond)
- bool run () override

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.82.1 Detailed Description

Waits until the condition is true.

## 5.82.2 Member Function Documentation

### 5.82.2.1 run()

```
bool WaitUntilCondition::run ( )  [inline], [override], [virtual]
```

Executes the command Overridden by child classes

**Returns**

true when the command is finished, false otherwise

Reimplemented from AutoCommand.

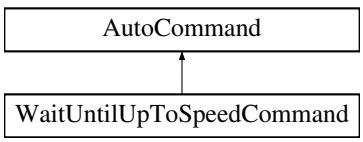
The documentation for this class was generated from the following file:

- include/utils/command_structure/auto_command.h

# 5.83 WaitUntilUpToSpeedCommand Class Reference

```
#include <flywheel_commands.h>
```

Inheritance diagram for WaitUntilUpToSpeedCommand:



#### Public Member Functions

- WaitUntilUpToSpeedCommand (Flywheel &flywheel, int threshold_rpm)
- bool run () override

### Public Member Functions inherited from AutoCommand

- virtual void on_timeout ()
- AutoCommand * **withTimeout** (double t_seconds)
- AutoCommand * **withCancelCondition** (Condition *true_to_end)

#### Additional Inherited Members

### Public Attributes inherited from AutoCommand

- double timeout_seconds = default_timeout
- Condition * **true_to_end** = nullptr

### Static Public Attributes inherited from AutoCommand

- static constexpr double **default_timeout** = 10.0

## 5.83.1 Detailed Description

AutoCommand that listens to the Flywheel and waits until it is at its target speed +/- the specified threshold

## 5.83.2 Constructor & Destructor Documentation

### 5.83.2.1 WaitUntilUpToSpeedCommand()

```
WaitUntilUpToSpeedCommand::WaitUntilUpToSpeedCommand (
            Flywheel & flywheel,
            int threshold_rpm )
```

Creat a WaitUntilUpToSpeedCommand

**Parameters**

| | |
|---|---|
| *flywheel* | the flywheel system we are commanding |
| *threshold_rpm* | the threshold over and under the flywheel target RPM that we define to be acceptable |

### 5.83.3 Member Function Documentation

#### 5.83.3.1 run()

```
bool WaitUntilUpToSpeedCommand::run ( )  [override], [virtual]
```

Run spin_manual Overrides run from AutoCommand

**Returns**

true when execution is complete, false otherwise

Reimplemented from AutoCommand.

The documentation for this class was generated from the following files:

- include/utils/command_structure/flywheel_commands.h
- src/utils/command_structure/flywheel_commands.cpp

# Chapter 6

# File Documentation

## 6.1 robot_specs.h

```
00001 #pragma once
00002 #include "../core/include/utils/controls/pid.h"
00003 #include "../core/include/utils/controls/feedback_base.h"
00004
00011 typedef struct
00012 {
00013   double robot_radius;
00014
00015   double odom_wheel_diam;
00016   double odom_gear_ratio;
00017   double dist_between_wheels;
00018
00019   double drive_correction_cutoff;
00020
00021   Feedback *drive_feedback;
00022   Feedback *turn_feedback;
00023   PID::pid_config_t correction_pid;
00024
00025 } robot_specs_t;
```

## 6.2 custom_encoder.h

```
00001 #pragma once
00002 #include "vex.h"
00003
00008 class CustomEncoder : public vex::encoder
00009 {
00010   typedef vex::encoder super;
00011
00012   public:
00018   CustomEncoder(vex::triport::port &port, double ticks_per_rev);
00019
00025   void setRotation(double val, vex::rotationUnits units);
00026
00032   void setPosition(double val, vex::rotationUnits units);
00033
00039   double rotation(vex::rotationUnits units);
00040
00046   double position(vex::rotationUnits units);
00047
00053   double velocity(vex::velocityUnits units);
00054
00055
00056   private:
00057   double tick_scalar;
00058 };
```

## 6.3 flywheel.h

```
00001 #pragma once
00002
00003 #include "../core/include/utils/controls/feedforward.h"
00004 #include "vex.h"
00005 #include "../core/include/robot_specs.h"
00006 #include "../core/include/utils/controls/pid.h"
00007 #include "../core/include/utils/command_structure/auto_command.h"
00008 #include "../core/include/subsystems/screen.h"
00009 #include <atomic>
00010
00018 class Flywheel
00019 {
00020
00021 public:
00022   // CONSTRUCTORS, GETTERS, AND SETTERS
00031   Flywheel(vex::motor_group &motors, Feedback &feedback, FeedForward &helper, const double ratio,
      Filter &filt);
00032
00037   double get_target() const;
00038
00042   double getRPM() const;
00043
00047   vex::motor_group &get_motors() const;
00048
00055   void spin_manual(double speed, directionType dir = fwd);
00056
00062   void spin_rpm(double rpm);
00063
00067   void stop();
00068
00073   bool is_on_target()
00074   {
00075     return fb.is_on_target();
00076   }
00077
00082   screen::Page *Page() const;
00083
00089   AutoCommand *SpinRpmCmd(int rpm)
00090   {
00091
00092     return new FunctionCommand([this, rpm]()
00093                                {spin_rpm(rpm); return true; });
00094   }
00095
00100   AutoCommand *WaitUntilUpToSpeedCmd()
00101   {
00102     return new WaitUntilCondition(
00103         new FunctionCondition([this]()
00104                               { return is_on_target(); }));
00105   }
00106
00107 private:
00108   friend class FlywheelPage;
00109   friend int spinRPMTask(void *wheelPointer);
00110
00111   vex::motor_group &motors;
00112   bool task_running = false;
00113   Feedback &fb;
00114   FeedForward &ff;
00115   vex::mutex fb_mut;
00116   double ratio;
00117   std::atomic<double> target_rpm;
00118   task rpm_task;
00119   Filter &avger;
00120
00121   // Functions for internal use only
00126   void set_target(double value);
00130   double measure_RPM();
00131
00138   void spin_raw(double speed, directionType dir = fwd);
00139 };
```

## 6.4 lift.h

```
00001 #pragma once
00002
00003 #include "vex.h"
00004 #include "../core/include/utils/controls/pid.h"
00005 #include <iostream>
00006 #include <map>
00007 #include <atomic>
```

```
00008 #include <vector>
00009
00010 using namespace vex;
00011 using namespace std;
00012
00020 template <typename T>
00021 class Lift
00022 {
00023   public:
00024
00031   struct lift_cfg_t
00032   {
00033     double up_speed, down_speed;
00034     double softstop_up, softstop_down;
00035
00036     PID::pid_config_t lift_pid_cfg;
00037   };
00038
00060   Lift(motor_group &lift_motors, lift_cfg_t &lift_cfg, map<T, double> &setpoint_map, limit
      *homing_switch=NULL)
00061   : lift_motors(lift_motors), cfg(lift_cfg), lift_pid(cfg.lift_pid_cfg), setpoint_map(setpoint_map),
      homing_switch(homing_switch)
00062   {
00063
00064     is_async = true;
00065     setpoint = 0;
00066
00067     // Create a background task that is constantly updating the lift PID, if requested.
00068     // Set once, and forget.
00069     task t([](void* ptr){
00070       Lift &lift = *((Lift*) ptr);
00071
00072       while(true)
00073       {
00074         if(lift.get_async())
00075           lift.hold();
00076
00077         vexDelay(50);
00078       }
00079
00080       return 0;
00081     }, this);
00082
00083   }
00084
00093   void control_continuous(bool up_ctrl, bool down_ctrl)
00094   {
00095     static timer tmr;
00096
00097     double cur_pos = 0;
00098
00099     // Check if there's a hook for a custom sensor. If not, use the motors.
00100     if(get_sensor == NULL)
00101       cur_pos = lift_motors.position(rev);
00102     else
00103       cur_pos = get_sensor();
00104
00105     if(up_ctrl && cur_pos < cfg.softstop_up)
00106     {
00107       lift_motors.spin(directionType::fwd, cfg.up_speed, volt);
00108       setpoint = cur_pos + .3;
00109
00110       // std::cout « "DEBUG OUT: UP " « setpoint « ", " « tmr.time(sec) « ", " « cfg.down_speed «
      "\n";
00111
00112       // Disable the PID while going UP.
00113       is_async = false;
00114     } else if(down_ctrl && cur_pos > cfg.softstop_down)
00115     {
00116       // Lower the lift slowly, at a rate defined by down_speed
00117       if(setpoint > cfg.softstop_down)
00118         setpoint = setpoint - (tmr.time(sec) * cfg.down_speed);
00119       // std::cout « "DEBUG OUT: DOWN " « setpoint « ", " « tmr.time(sec) « ", " « cfg.down_speed «
      "\n";
00120       is_async = true;
00121     } else
00122     {
00123       // Hold the lift at the last setpoint
00124       is_async = true;
00125     }
00126
00127     tmr.reset();
00128   }
00129
00138   void control_manual(bool up_btn, bool down_btn, int volt_up, int volt_down)
00139   {
00140     static bool down_hold = false;
```

```
00141     static bool init = true;
00142
00143     // Allow for setting position while still calling this function
00144     if(init || up_btn || down_btn)
00145     {
00146       init = false;
00147       is_async = false;
00148     }
00149
00150     double rev = lift_motors.position(rotationUnits::rev);
00151
00152     if(rev < cfg.softstop_down && down_btn)
00153       down_hold = true;
00154     else if( !down_btn )
00155       down_hold = false;
00156
00157     if(up_btn && rev < cfg.softstop_up)
00158       lift_motors.spin(directionType::fwd, volt_up, voltageUnits::volt);
00159     else if(down_btn && rev > cfg.softstop_down && !down_hold)
00160       lift_motors.spin(directionType::rev, volt_down, voltageUnits::volt);
00161     else
00162       lift_motors.spin(directionType::fwd, 0, voltageUnits::volt);
00163
00164   }
00165
00177   void control_setpoints(bool up_step, bool down_step, vector<T> pos_list)
00178   {
00179     // Make sure inputs are only processed on the rising edge of the button
00180     static bool up_last = up_step, down_last = down_step;
00181
00182     bool up_rising = up_step && !up_last;
00183     bool down_rising = down_step && !down_last;
00184
00185     up_last = up_step;
00186     down_last = down_step;
00187
00188     static int cur_index = 0;
00189
00190     // Avoid an index overflow. Shouldn't happen unless the user changes pos_list between calls.
00191     if(cur_index >= pos_list.size())
00192       cur_index = pos_list.size() - 1;
00193
00194     // Increment or decrement the index of the list, bringing it up or down.
00195     if(up_rising && cur_index < (pos_list.size() - 1))
00196       cur_index++;
00197     else if(down_rising && cur_index > 0)
00198       cur_index--;
00199
00200     // Set the lift to hold the position in the background with the PID loop
00201     set_position(pos_list[cur_index]);
00202     is_async = true;
00203
00204   }
00205
00214   bool set_position(T pos)
00215   {
00216     this->setpoint = setpoint_map[pos];
00217     is_async = true;
00218
00219     return (lift_pid.get_target() == this->setpoint) && lift_pid.is_on_target();
00220   }
00221
00228   bool set_setpoint(double val)
00229   {
00230     this->setpoint = val;
00231     return (lift_pid.get_target() == this->setpoint) && lift_pid.is_on_target();
00232   }
00233
00237   double get_setpoint()
00238   {
00239     return this->setpoint;
00240   }
00241
00246   void hold()
00247   {
00248     lift_pid.set_target(setpoint);
00249     // std::cout << "DEBUG OUT: SETPOINT " << setpoint << "\n";
00250
00251     if(get_sensor != NULL)
00252       lift_pid.update(get_sensor());
00253     else
00254       lift_pid.update(lift_motors.position(rev));
00255
00256     // std::cout << "DEBUG OUT: ROTATION " << lift_motors.rotation(rev) << "\n\n";
00257
00258     lift_motors.spin(fwd, lift_pid.get(), volt);
00259   }
```

```
00260
00265   void home()
00266   {
00267     static timer tmr;
00268     tmr.reset();
00269
00270     while(tmr.time(sec) < 3)
00271     {
00272       lift_motors.spin(directionType::rev, 6, volt);
00273
00274       if (homing_switch == NULL && lift_motors.current(currentUnits::amp) > 1.5)
00275         break;
00276       else if (homing_switch != NULL && homing_switch->pressing())
00277         break;
00278     }
00279
00280     if(reset_sensor != NULL)
00281       reset_sensor();
00282
00283     lift_motors.resetPosition();
00284     lift_motors.stop();
00285
00286   }
00287
00291   bool get_async()
00292   {
00293     return is_async;
00294   }
00295
00301   void set_async(bool val)
00302   {
00303     this->is_async = val;
00304   }
00305
00315   void set_sensor_function(double (*fn_ptr) (void))
00316   {
00317     this->get_sensor = fn_ptr;
00318   }
00319
00326   void set_sensor_reset(void (*fn_ptr) (void))
00327   {
00328     this->reset_sensor = fn_ptr;
00329   }
00330
00331   private:
00332
00333   motor_group &lift_motors;
00334   lift_cfg_t &cfg;
00335   PID lift_pid;
00336   map<T, double> &setpoint_map;
00337   limit *homing_switch;
00338
00339   atomic<double> setpoint;
00340   atomic<bool> is_async;
00341
00342   double (*get_sensor)(void) = NULL;
00343   void (*reset_sensor)(void) = NULL;
00344
00345
00346 };
```

## 6.5 mecanum_drive.h

```
00001 #pragma once
00002
00003 #include "vex.h"
00004 #include "../core/include/utils/controls/pid.h"
00005
00006 #ifndef PI
00007 #define PI 3.141592654
00008 #endif
00009
00014 class MecanumDrive
00015 {
00016
00017   public:
00018
00022   struct mecanumdrive_config_t
00023   {
00024     // PID configurations for autonomous driving
00025     PID::pid_config_t drive_pid_conf;
00026     PID::pid_config_t drive_gyro_pid_conf;
00027     PID::pid_config_t turn_pid_conf;
```

```
00028
00029     // Diameter of the mecanum wheels
00030     double drive_wheel_diam;
00031
00032     // Diameter of the perpendicular undriven encoder wheel
00033     double lateral_wheel_diam;
00034
00035     // Width between the center of the left and right wheels
00036     double wheelbase_width;
00037
00038   };
00039
00043   MecanumDrive(vex::motor &left_front, vex::motor &right_front, vex::motor &left_rear, vex::motor
      &right_rear,
00044                vex::rotation *lateral_wheel=NULL, vex::inertial *imu=NULL, mecanumdrive_config_t
      *config=NULL);
00045
00054   void drive_raw(double direction_deg, double magnitude, double rotation);
00055
00066   void drive(double left_y, double left_x, double right_x, int power=2);
00067
00080   bool auto_drive(double inches, double direction, double speed, bool gyro_correction=true);
00081
00092   bool auto_turn(double degrees, double speed, bool ignore_imu=false);
00093
00094   private:
00095
00096   vex::motor &left_front, &right_front, &left_rear, &right_rear;
00097
00098   mecanumdrive_config_t *config;
00099   vex::rotation *lateral_wheel;
00100   vex::inertial *imu;
00101
00102   PID *drive_pid = NULL;
00103   PID *drive_gyro_pid = NULL;
00104   PID *turn_pid = NULL;
00105
00106   bool init = true;
00107
00108 };
```

## 6.6 odometry_3wheel.h

```
00001 #pragma once
00002 #include "../core/include/subsystems/odometry/odometry_base.h"
00003 #include "../core/include/subsystems/tank_drive.h"
00004 #include "../core/include/subsystems/custom_encoder.h"
00005
00032 class Odometry3Wheel : public OdometryBase
00033 {
00034     public:
00035
00040     typedef struct
00041     {
00042         double wheelbase_dist;
00043         double off_axis_center_dist;
00044         double wheel_diam;
00046     } odometry3wheel_cfg_t;
00047
00057     Odometry3Wheel(CustomEncoder &lside_fwd, CustomEncoder &rside_fwd, CustomEncoder &off_axis,
      odometry3wheel_cfg_t &cfg, bool is_async=true);
00058
00065     pose_t update() override;
00066
00075     void tune(vex::controller &con, TankDrive &drive);
00076
00077     private:
00078
00091     static pose_t calculate_new_pos(double lside_delta_deg, double rside_delta_deg, double
      offax_delta_deg, pose_t old_pos, odometry3wheel_cfg_t cfg);
00092
00093     CustomEncoder &lside_fwd, &rside_fwd, &off_axis;
00094     odometry3wheel_cfg_t &cfg;
00095
00096
00097 };
```

## 6.7 odometry_base.h

```
00001 #pragma once
```

```
00002
00003 #include "vex.h"
00004 #include "../core/include/utils/geometry.h"
00005 #include "../core/include/robot_specs.h"
00006
00007 #ifndef PI
00008 #define PI 3.141592654
00009 #endif
00010
00011
00012
00025 class OdometryBase
00026 {
00027 public:
00028
00034     OdometryBase(bool is_async);
00035
00040     pose_t get_position(void);
00041
00046     virtual void set_position(const pose_t& newpos=zero_pos);
00047
00052     virtual pose_t update() = 0;
00053
00061     static int background_task(void* ptr);
00062
00068     void end_async();
00069
00076     static double pos_diff(pose_t start_pos, pose_t end_pos);
00077
00084     static double rot_diff(pose_t pos1, pose_t pos2);
00085
00094     static double smallest_angle(double start_deg, double end_deg);
00095
00097     bool end_task = false;
00098
00103     double get_speed();
00104
00109     double get_accel();
00110
00115     double get_angular_speed_deg();
00116
00121     double get_angular_accel_deg();
00122
00126     inline static constexpr pose_t zero_pos = {.x=0.0L, .y=0.0L, .rot=90.0L};
00127
00128 protected:
00132     vex::task *handle;
00133
00137     vex::mutex mut;
00138
00142     pose_t current_pos;
00143
00144     double speed;
00145     double accel;
00146     double ang_speed_deg;
00147     double ang_accel_deg;
00148 };
```

## 6.8 odometry_tank.h

```
00001 #pragma once
00002
00003 #include "../core/include/subsystems/odometry/odometry_base.h"
00004 #include "../core/include/subsystems/custom_encoder.h"
00005 #include "../core/include/utils/geometry.h"
00006 #include "../core/include/utils/vector2d.h"
00007 #include "../core/include/robot_specs.h"
00008
00009 static int background_task(void* odom_obj);
00010
00011
00018 class OdometryTank : public OdometryBase
00019 {
00020 public:
00029     OdometryTank(vex::motor_group &left_side, vex::motor_group &right_side, robot_specs_t &config,
      vex::inertial *imu=NULL, bool is_async=true);
00030
00040     OdometryTank(CustomEncoder &left_custom_enc, CustomEncoder &right_custom_enc, robot_specs_t
      &config, vex::inertial *imu=NULL, bool is_async=true);
00041
00051     OdometryTank(vex::encoder &left_vex_enc, vex::encoder &right_vex_enc, robot_specs_t &config,
      vex::inertial *imu=NULL, bool is_async=true);
00052
```

```
00057     pose_t update() override;
00058
00063     void set_position(const pose_t &newpos=zero_pos) override;
00064
00065
00066
00067 private:
00071     static pose_t calculate_new_pos(robot_specs_t &config, pose_t &stored_info, double lside_diff,
      double rside_diff, double angle_deg);
00072
00073     vex::motor_group *left_side, *right_side;
00074     CustomEncoder *left_custom_enc, *right_custom_enc;
00075     vex::encoder *left_vex_enc, *right_vex_enc;
00076     vex::inertial *imu;
00077     robot_specs_t &config;
00078
00079     double rotation_offset = 0;
00080
00081 };
```

## 6.9 screen.h

```
00001 #pragma once
00002 #include "vex.h"
00003 #include <vector>
00004 #include <functional>
00005 #include <map>
00006 #include <cassert>
00007 #include "../core/include/subsystems/odometry/odometry_base.h"
00008 #include "../core/include/utils/graph_drawer.h"
00009 #include "../core/include/utils/controls/pid.h"
00010 #include "../core/include/utils/controls/pidff.h"
00011
00012 namespace screen
00013 {
00015     class Page
00016     {
00017     public:
00026         virtual void update(bool was_pressed, int x, int y);
00034         virtual void draw(vex::brain::lcd &screen, bool first_draw,
00035                           unsigned int frame_number);
00036     };
00037
00039     class SliderWidget
00040     {
00041     public:
00048         SliderWidget(double &val, double low, double high, Rect rect, std::string name) : value(val),
      low(low), high(high), rect(rect), name(name) {}
00049
00055         bool update(bool was_pressed, int x, int y);
00057         void draw(vex::brain::lcd &, bool first_draw, unsigned int frame_number);
00058
00059     private:
00060         double &value;
00061
00062         double low;
00063         double high;
00064
00065         Rect rect;
00066         std::string name = "";
00067     };
00068
00070     class ButtonWidget
00071     {
00072     public:
00077         ButtonWidget(std::function<void(void)> onpress, Rect rect, std::string name) :
      onpress(onpress), rect(rect), name(name) {}
00082         ButtonWidget(void (*onpress)(), Rect rect, std::string name) : onpress(onpress), rect(rect),
      name(name) {}
00083
00089         bool update(bool was_pressed, int x, int y);
00091         void draw(vex::brain::lcd &, bool first_draw, unsigned int frame_number);
00092
00093     private:
00094         std::function<void(void)> onpress;
00095         Rect rect;
00096         std::string name = "";
00097         bool was_pressed_last = false;
00098     };
00099
00106     void start_screen(vex::brain::lcd &screen, std::vector<Page *> pages, int first_page = 0);
00107
00109     void stop_screen();
```

```
00110
00112     using update_func_t = std::function<void(bool, int, int)>;
00113
00115     using draw_func_t = std::function<void(vex::brain::lcd &screen, bool, unsigned int)>;
00116
00117
00119     class StatsPage : public Page
00120     {
00121     public:
00124         StatsPage(std::map<std::string, vex::motor &> motors);
00126         void update(bool was_pressed, int x, int y) override;
00128         void draw(vex::brain::lcd &, bool first_draw, unsigned int frame_number) override;
00129
00130     private:
00131         void draw_motor_stats(const std::string &name, vex::motor &mot, unsigned int frame, int x, int
      y, vex::brain::lcd &scr);
00132
00133         std::map<std::string, vex::motor &> motors;
00134         static const int y_start = 0;
00135         static const int per_column = 4;
00136         static const int row_height = 20;
00137         static const int row_width = 200;
00138     };
00139
00143     class OdometryPage : public Page
00144     {
00145     public:
00151         OdometryPage(OdometryBase &odom, double robot_width, double robot_height, bool do_trail);
00153         void update(bool was_pressed, int x, int y) override;
00155         void draw(vex::brain::lcd &, bool first_draw, unsigned int frame_number) override;
00156
00157     private:
00158         static const int path_len = 40;
00159         static constexpr char const *field_filename = "vex_field_240p.png";
00160
00161         OdometryBase &odom;
00162         double robot_width;
00163         double robot_height;
00164         uint8_t *buf = nullptr;
00165         int buf_size = 0;
00166         pose_t path[path_len];
00167         int path_index = 0;
00168         bool do_trail;
00169     };
00170
00172     class FunctionPage : public Page
00173     {
00174     public:
00178         FunctionPage(update_func_t update_f, draw_func_t draw_t);
00180         void update(bool was_pressed, int x, int y) override;
00182         void draw(vex::brain::lcd &, bool first_draw, unsigned int frame_number) override;
00183
00184     private:
00185         update_func_t update_f;
00186         draw_func_t draw_f;
00187     };
00188
00190     class PIDPage : public Page
00191     {
00192     public:
00197         PIDPage(PID &pid, std::string name, std::function<void(void)> onchange = [](){});
00198         PIDPage(PIDFF &pidff, std::string name, std::function<void(void)> onchange = [](){});
00199
00201         void update(bool was_pressed, int x, int y) override;
00203         void draw(vex::brain::lcd &, bool first_draw, unsigned int frame_number) override;
00204
00205     private:
00207         void zero_d_f() { cfg.d = 0; }
00209         void zero_i_f() { cfg.i = 0; }
00210
00211         PID::pid_config_t &cfg;
00212         PID &pid;
00213         const std::string name;
00214         std::function<void(void)> onchange;
00215
00216         SliderWidget p_slider;
00217         SliderWidget i_slider;
00218         SliderWidget d_slider;
00219         ButtonWidget zero_i;
00220         ButtonWidget zero_d;
00221
00222         GraphDrawer graph;
00223     };
00224
00225 }
```

## 6.10 tank_drive.h

```
00001 #pragma once
00002
00003 #ifndef PI
00004 #define PI 3.141592654
00005 #endif
00006
00007 #include "vex.h"
00008 #include "../core/include/subsystems/odometry/odometry_tank.h"
00009 #include "../core/include/utils/controls/pid.h"
00010 #include "../core/include/utils/controls/feedback_base.h"
00011 #include "../core/include/robot_specs.h"
00012 #include "../core/include/utils/pure_pursuit.h"
00013 #include "../core/include/utils/command_structure/auto_command.h"
00014 #include <vector>
00015
00016 using namespace vex;
00017
00022 class TankDrive
00023 {
00024 public:
00032   TankDrive(motor_group &left_motors, motor_group &right_motors, robot_specs_t &config, OdometryBase
      *odom = NULL);
00033
00034   AutoCommand *DriveToPointCmd(point_t pt, vex::directionType dir = vex::forward, double max_speed =
      1.0, double end_speed = 0.0);
00035   AutoCommand *DriveToPointCmd(Feedback &fb, point_t pt, vex::directionType dir = vex::forward, double
      max_speed = 1.0, double end_speed = 0.0);
00036
00037   AutoCommand *DriveForwardCmd(double dist, vex::directionType dir = vex::forward, double max_speed =
      1.0, double end_speed = 0.0);
00038   AutoCommand *DriveForwardCmd(Feedback &fb, double dist, vex::directionType dir = vex::forward,
      double max_speed = 1.0, double end_speed = 0.0);
00039
00040   AutoCommand *TurnToHeadingCmd(double heading, double max_speed = 1.0, double end_speed = 0.0);
00041   AutoCommand *TurnToHeadingCmd(Feedback &fb, double heading, double max_speed = 1.0, double end_speed
      = 0.0);
00042
00043   AutoCommand *TurnDegreesCmd(double degrees, double max_speed = 1.0, double start_speed = 0.0);
00044   AutoCommand *TurnDegreesCmd(Feedback &fb, double degrees, double max_speed = 1.0, double end_speed =
      0.0);
00045
00046   AutoCommand *PurePursuitCmd(PurePursuit::Path path, directionType dir, double max_speed=1, double
      end_speed=0);
00047   AutoCommand *PurePursuitCmd(Feedback &feedback, PurePursuit::Path path, directionType dir, double
      max_speed=1, double end_speed=0);
00048
00052   void stop();
00053
00064   void drive_tank(double left, double right, int power=1);
00065
00076   void drive_arcade(double forward_back, double left_right, int power = 1);
00077
00089   bool drive_forward(double inches, directionType dir, Feedback &feedback, double max_speed = 1,
      double end_speed = 0);
00090
00100   bool drive_forward(double inches, directionType dir, double max_speed = 1, double end_speed = 0);
00101
00112   bool turn_degrees(double degrees, Feedback &feedback, double max_speed = 1, double end_speed = 0);
00113
00124   bool turn_degrees(double degrees, double max_speed = 1, double end_speed = 0);
00125
00138   bool drive_to_point(double x, double y, vex::directionType dir, Feedback &feedback, double max_speed
      = 1, double end_speed = 0);
00139
00152   bool drive_to_point(double x, double y, vex::directionType dir, double max_speed = 1, double
      end_speed = 0);
00153
00163   bool turn_to_heading(double heading_deg, Feedback &feedback, double max_speed = 1, double end_speed
      = 0);
00172   bool turn_to_heading(double heading_deg, double max_speed = 1, double end_speed = 0);
00173
00177   void reset_auto();
00178
00187   static double modify_inputs(double input, int power = 2);
00188
00201   bool pure_pursuit(PurePursuit::Path path, directionType dir, Feedback &feedback, double max_speed=1,
      double end_speed=0);
00202
00216   bool pure_pursuit(PurePursuit::Path path, directionType dir, double max_speed=1, double
      end_speed=0);
00217
00218 private:
00219   motor_group &left_motors;
00220   motor_group &right_motors;
00221
```

```
00222   PID correction_pid;
00223   Feedback *drive_default_feedback = NULL;
00224   Feedback *turn_default_feedback = NULL;
00225
00226   OdometryBase *odometry;
00227
00228   robot_specs_t &config;
00229
00230   bool func_initialized = false;
00231   bool is_pure_pursuit = false;
00232 };
```

## 6.11 auto_chooser.h

```
00001 #pragma once
00002 #include "vex.h"
00003 #include <string>
00004 #include <vector>
00005 #include "../core/include/subsystems/screen.h"
00006 #include "../core/include/utils/geometry.h"
00007
00016 class AutoChooser : public screen::Page
00017 {
00018 public:
00024   AutoChooser(std::vector<std::string> paths, size_t def = 0);
00025
00026   void update(bool was_pressed, int x, int y);
00027   void draw(vex::brain::lcd &, bool first_draw, unsigned int frame_number);
00028
00033   size_t get_choice();
00034
00035 protected:
00039   struct entry_t
00040   {
00041     Rect rect;
00042     std::string name;
00043   };
00044
00045   static const size_t width = 380;
00046   static const size_t height = 220;
00047
00048   size_t choice;
00049   std::vector<entry_t> list ;
00050 };
```

## 6.12 auto_command.h

```
00001
00007 #pragma once
00008
00009 #include "vex.h"
00010 #include <functional>
00011 #include <vector>
00012 #include <queue>
00013 #include <atomic>
00014
00015
00025 class Condition
00026 {
00027 public:
00028   Condition *Or(Condition *b);
00029   Condition *And(Condition *b);
00030   virtual bool test() = 0;
00031 };
00032
00033
00034 class AutoCommand
00035 {
00036 public:
00037   static constexpr double default_timeout = 10.0;
00043   virtual bool run() { return true; }
00047   virtual void on_timeout() {}
00048   AutoCommand *withTimeout(double t_seconds)
00049   {
00050     if (this->timeout_seconds < 0)
00051     {
00052       // should never be timed out
00053       return this;
00054     }
```

```
00055     this->timeout_seconds = t_seconds;
00056     return this;
00057   }
00058   AutoCommand *withCancelCondition(Condition *true_to_end){
00059     this->true_to_end = true_to_end;
00060     return this;
00061   }
00071   double timeout_seconds = default_timeout;
00072   Condition *true_to_end = nullptr;
00073 };
00074
00079 class FunctionCommand : public AutoCommand
00080 {
00081 public:
00082   FunctionCommand(std::function<bool(void)> f) : f(f) {}
00083   bool run()
00084   {
00085     return f();
00086   }
00087
00088 private:
00089   std::function<bool(void)> f;
00090 };
00091
00092 // Times tested 3
00093 // Test 1 -> false
00094 // Test 2 -> false
00095 // Test 3 -> true
00096 // Returns false until the Nth time that it is called
00097 // This is pretty much only good for implementing RepeatUntil
00098 class TimesTestedCondition : public Condition
00099 {
00100 public:
00101   TimesTestedCondition(size_t N) : max(N) {}
00102   bool test() override
00103   {
00104     count++;
00105     if (count >= max)
00106     {
00107       return true;
00108     }
00109     return false;
00110   }
00111
00112 private:
00113   size_t count = 0;
00114   size_t max;
00115 };
00116
00118 class FunctionCondition : public Condition
00119 {
00120 public:
00121   FunctionCondition(
00122       std::function<bool()> cond, std::function<void(void)> timeout = []() {}) : cond(cond),
     timeout(timeout)
00123   {
00124   }
00125   bool test() override;
00126
00127 private:
00128   std::function<bool()> cond;
00129   std::function<void(void)> timeout;
00130 };
00131
00133 class IfTimePassed : public Condition
00134 {
00135 public:
00136   IfTimePassed(double time_s);
00137   bool test() override;
00138
00139 private:
00140   double time_s;
00141   vex::timer tmr;
00142 };
00143
00145 class WaitUntilCondition : public AutoCommand
00146 {
00147 public:
00148   WaitUntilCondition(Condition *cond) : cond(cond) {}
00149   bool run() override
00150   {
00151     return cond->test();
00152   }
00153
00154 private:
00155   Condition *cond;
00156 };
```

```
00157
00160
00163 class InOrder : public AutoCommand
00164 {
00165 public:
00166   InOrder(const InOrder &other) = default;
00167   InOrder(std::queue<AutoCommand *> cmds);
00168   InOrder(std::initializer_list<AutoCommand *> cmds);
00169   bool run() override;
00170   void on_timeout() override;
00171
00172 private:
00173   AutoCommand *current_command = nullptr;
00174   std::queue<AutoCommand *> cmds;
00175   vex::timer tmr;
00176 };
00177
00180 class Parallel : public AutoCommand
00181 {
00182 public:
00183   Parallel(std::initializer_list<AutoCommand *> cmds);
00184   bool run() override;
00185   void on_timeout() override;
00186
00187 private:
00188   std::vector<AutoCommand *> cmds;
00189   std::vector<vex::task *> runners;
00190 };
00191
00195 class Branch : public AutoCommand
00196 {
00197 public:
00198   Branch(Condition *cond, AutoCommand *false_choice, AutoCommand *true_choice);
00199   ~Branch();
00200   bool run() override;
00201   void on_timeout() override;
00202
00203 private:
00204   AutoCommand *false_choice;
00205   AutoCommand *true_choice;
00206   Condition *cond;
00207   bool choice = false;
00208   bool chosen = false;
00209   vex::timer tmr;
00210 };
00211
00215 class Async : public AutoCommand
00216 {
00217 public:
00218   Async(AutoCommand *cmd) : cmd(cmd) {}
00219   bool run() override;
00220
00221 private:
00222   AutoCommand *cmd = nullptr;
00223 };
00224
00225 class RepeatUntil : public AutoCommand
00226 {
00227 public:
00231   RepeatUntil(InOrder cmds, size_t repeats);
00235   RepeatUntil(InOrder cmds, Condition *true_to_end);
00236   bool run() override;
00237   void on_timeout() override;
00238
00239 private:
00240   const InOrder cmds;
00241   InOrder *working_cmds;
00242   Condition *cond;
00243 };
```

## 6.13 basic_command.h

```
00001
00014 #pragma once
00015
00016 #include "../core/include/utils/command_structure/auto_command.h"
00017
00018 //Basic Motor Classes-----------------------------------------------
00019
00024 class BasicSpinCommand : public AutoCommand {
00025     public:
00026
00027      //Enumurator for the type of power setting in the motor
```

```
00028      enum type {percent,voltage,veocity};
00029
00038      BasicSpinCommand(vex::motor &motor, vex::directionType dir, BasicSpinCommand::type setting,
      double power);
00039
00046      bool run() override;
00047
00048     private:
00049
00050      vex::motor &motor;
00051
00052      type setting;
00053
00054      vex::directionType dir;
00055
00056      double power;
00057 };
00062 class BasicStopCommand : public AutoCommand{
00063     public:
00064
00071      BasicStopCommand(vex::motor &motor, vex::brakeType setting);
00072
00079      bool run() override;
00080
00081     private:
00082
00083      vex::motor &motor;
00084
00085      vex::brakeType setting;
00086 };
00087
00088 //Basic Solenoid Commands--------------------------------
00089
00094 class BasicSolenoidSet : public AutoCommand{
00095     public:
00096
00103      BasicSolenoidSet(vex::pneumatics &solenoid, bool setting);
00104
00111      bool run() override;
00112
00113     private:
00114
00115      vex::pneumatics &solenoid;
00116
00117      bool setting;
00118 };
```

## 6.14 command_controller.h

```
00001
00010 #pragma once
00011 #include <vector>
00012 #include <queue>
00013 #include "../core/include/utils/command_structure/auto_command.h"
00014
00015 class CommandController
00016 {
00017 public:
00019   [[deprecated("Use list constructor instead.")]] CommandController() : command_queue({}) {}
00020
00023   CommandController(std::initializer_list<AutoCommand *> cmds) : command_queue(cmds) {}
00029   [[deprecated("Use list constructor instead. If you need to make a decision before adding new
      commands, use Branch (https://github.com/RIT-VEX-U/Core/wiki/3-%7C-Utilites#commandcontroller)")]]
      void add(std::vector<AutoCommand *> cmds);
00030   void add(AutoCommand *cmd, double timeout_seconds = 10.0);
00031
00042   [[deprecated("Use list constructor instead. If you need to make a decision before adding new
      commands, use Branch (https://github.com/RIT-VEX-U/Core/wiki/3-%7C-Utilites#commandcontroller)")]]
      void
00043   add(std::vector<AutoCommand *> cmds, double timeout_sec);
00050   void add_delay(int ms);
00051
00054   void add_cancel_func(std::function<bool(void)> true_if_cancel);
00055
00060   void run();
00061
00067   bool last_command_timed_out();
00068
00069 private:
00070   std::queue<AutoCommand *> command_queue;
00071   bool command_timed_out = false;
00072   std::function<bool()> should_cancel = []()
00073   { return false; };
00074 };
```

## 6.15 delay_command.h

```
00001
00008 #pragma once
00009
00010 #include "../core/include/utils/command_structure/auto_command.h"
00011
00012 class DelayCommand: public AutoCommand {
00013   public:
00018     DelayCommand(int ms): ms(ms) {}
00019
00025     bool run() override {
00026       vexDelay(ms);
00027       return true;
00028     }
00029
00030   private:
00031     // amount of milliseconds to wait
00032     int ms;
00033 };
```

## 6.16 drive_commands.h

```
00001
00019 #pragma once
00020
00021 #include "vex.h"
00022 #include "../core/include/utils/geometry.h"
00023 #include "../core/include/utils/command_structure/auto_command.h"
00024 #include "../core/include/subsystems/tank_drive.h"
00025
00026 using namespace vex;
00027
00028
00029 // ==== DRIVING ====
00030
00036 class DriveForwardCommand: public AutoCommand
00037 {
00038   public:
00039     DriveForwardCommand(TankDrive &drive_sys, Feedback &feedback, double inches, directionType dir,
      double max_speed=1, double end_speed=0);
00040
00046     bool run() override;
00050     void on_timeout() override;
00051
00052   private:
00053     // drive system to run the function on
00054     TankDrive &drive_sys;
00055
00056     // feedback controller to use
00057     Feedback &feedback;
00058
00059     // parameters for drive_forward
00060     double inches;
00061     directionType dir;
00062     double max_speed;
00063     double end_speed;
00064 };
00065
00070 class TurnDegreesCommand: public AutoCommand
00071 {
00072   public:
00073     TurnDegreesCommand(TankDrive &drive_sys, Feedback &feedback, double degrees, double max_speed = 1,
      double end_speed = 0);
00074
00080     bool run() override;
00084     void on_timeout() override;
00085
00086
00087   private:
00088     // drive system to run the function on
00089     TankDrive &drive_sys;
00090
00091     // feedback controller to use
00092     Feedback &feedback;
00093
00094     // parameters for turn_degrees
00095     double degrees;
00096     double max_speed;
00097     double end_speed;
00098 };
00099
00104 class DriveToPointCommand: public AutoCommand
```

```
00105 {
00106   public:
00107     DriveToPointCommand(TankDrive &drive_sys, Feedback &feedback, double x, double y, directionType
      dir, double max_speed = 1, double end_speed = 0);
00108     DriveToPointCommand(TankDrive &drive_sys, Feedback &feedback, point_t point, directionType dir,
      double max_speed=1, double end_speed = 0);
00109
00115     bool run() override;
00116
00117   private:
00118     // drive system to run the function on
00119     TankDrive &drive_sys;
00120
00124     void on_timeout() override;
00125
00126
00127     // feedback controller to use
00128     Feedback &feedback;
00129
00130     // parameters for drive_to_point
00131     double x;
00132     double y;
00133     directionType dir;
00134     double max_speed;
00135     double end_speed;
00136
00137 };
00138
00144 class TurnToHeadingCommand: public AutoCommand
00145 {
00146   public:
00147     TurnToHeadingCommand(TankDrive &drive_sys, Feedback &feedback, double heading_deg, double speed =
      1, double end_speed = 0);
00148
00154     bool run() override;
00158     void on_timeout() override;
00159
00160
00161   private:
00162     // drive system to run the function on
00163     TankDrive &drive_sys;
00164
00165     // feedback controller to use
00166     Feedback &feedback;
00167
00168     // parameters for turn_to_heading
00169     double heading_deg;
00170     double max_speed;
00171     double end_speed;
00172 };
00173
00177 class PurePursuitCommand: public AutoCommand
00178 {
00179   public:
00188   PurePursuitCommand(TankDrive &drive_sys, Feedback &feedback, PurePursuit::Path path, directionType
      dir, double max_speed=1, double end_speed=0);
00189
00193   bool run() override;
00194
00198   void on_timeout() override;
00199
00200   private:
00201   TankDrive &drive_sys;
00202   PurePursuit::Path path;
00203   directionType dir;
00204   Feedback &feedback;
00205   double max_speed;
00206   double end_speed;
00207
00208 };
00209
00214 class DriveStopCommand: public AutoCommand
00215 {
00216   public:
00217     DriveStopCommand(TankDrive &drive_sys);
00218
00224     bool run() override;
00225     void on_timeout() override;
00226
00227   private:
00228     // drive system to run the function on
00229     TankDrive &drive_sys;
00230 };
00231
00232
00233 // ==== ODOMETRY ====
00234
```

```
00239 class OdomSetPosition: public AutoCommand
00240 {
00241   public:
00247     OdomSetPosition(OdometryBase &odom, const pose_t &newpos=OdometryBase::zero_pos);
00248
00254     bool run() override;
00255
00256   private:
00257     // drive system with an odometry config
00258     OdometryBase &odom;
00259     pose_t newpos;
00260 };
```

## 6.17 flywheel_commands.h

```
00001
00007 #pragma once
00008
00009 #include "../core/include/subsystems/flywheel.h"
00010 #include "../core/include/utils/command_structure/auto_command.h"
00011
00017 class SpinRPMCommand: public AutoCommand {
00018   public:
00024   SpinRPMCommand(Flywheel &flywheel, int rpm);
00025
00031     bool run() override;
00032
00033   private:
00034     // Flywheel instance to run the function on
00035     Flywheel &flywheel;
00036
00037     // parameters for spin_rpm
00038     int rpm;
00039 };
00040
00045 class WaitUntilUpToSpeedCommand: public AutoCommand {
00046   public:
00052     WaitUntilUpToSpeedCommand(Flywheel &flywheel, int threshold_rpm);
00053
00059     bool run() override;
00060
00061   private:
00062     // Flywheel instance to run the function on
00063     Flywheel &flywheel;
00064
00065     // if the actual speed is equal to the desired speed +/- this value, we are ready to fire
00066     int threshold_rpm;
00067 };
00068
00074 class FlywheelStopCommand: public AutoCommand {
00075   public:
00080   FlywheelStopCommand(Flywheel &flywheel);
00081
00087     bool run() override;
00088
00089   private:
00090     // Flywheel instance to run the function on
00091     Flywheel &flywheel;
00092 };
00093
00099 class FlywheelStopMotorsCommand: public AutoCommand {
00100   public:
00105   FlywheelStopMotorsCommand(Flywheel &flywheel);
00106
00112     bool run() override;
00113
00114   private:
00115     // Flywheel instance to run the function on
00116     Flywheel &flywheel;
00117 };
00118
00124 class FlywheelStopNonTasksCommand: public AutoCommand {
00125   FlywheelStopNonTasksCommand(Flywheel &flywheel);
00126
00132     bool run() override;
00133
00134   private:
00135     // Flywheel instance to run the function on
00136     Flywheel &flywheel;
00137 };
```

## 6.18 bang_bang.h

```
00001 #include "../core/include/utils/controls/feedback_base.h"
00002
00003 class BangBang : public Feedback
00004 {
00005
00006 public:
00007     BangBang(double thresshold, double low, double high);
00016     void init(double start_pt, double set_pt, double start_vel [[maybe_unused]] = 0.0, double end_vel
      [[maybe_unused]] = 0.0) override;
00017
00024     double update(double val) override;
00025
00029     double get() override;
00030
00037     void set_limits(double lower, double upper) override;
00038
00042     bool is_on_target() override;
00043
00044 private:
00045     double setpt;
00046     double sensor_val;
00047     double lower_bound, upper_bound;
00048     double last_output;
00049     double threshhold;
00050 };
```

## 6.19 feedback_base.h

```
00001 #pragma once
00002
00010 class Feedback
00011 {
00012 public:
00021     virtual void init(double start_pt, double set_pt, double start_vel = 0.0, double end_vel = 0.0) =
      0;
00022
00029     virtual double update(double val) = 0;
00030
00034     virtual double get() = 0;
00035
00042     virtual void set_limits(double lower, double upper) = 0;
00043
00047     virtual bool is_on_target() = 0;
00048
00049
00050 };
```

## 6.20 feedforward.h

```
00001 #pragma once
00002
00003 #include <math.h>
00004 #include <vector>
00005 #include "../core/include/utils/math_util.h"
00006 #include "../core/include/utils/moving_average.h"
00007 #include "vex.h"
00008
00029 class FeedForward
00030 {
00031     public:
00032
00041     typedef struct
00042     {
00043         double kS;
00044         double kV;
00045         double kA;
00046         double kG;
00047     } ff_config_t;
00048
00049
00054     FeedForward(ff_config_t &cfg) : cfg(cfg) {}
00055
00066     double calculate(double v, double a, double pid_ref=0.0)
00067     {
00068         double ks_sign = 0;
00069         if(v != 0)
00070             ks_sign = sign(v);
```

```
00071         else if(pid_ref != 0)
00072             ks_sign = sign(pid_ref);
00073 
00074         return (cfg.kS * ks_sign) + (cfg.kV * v) + (cfg.kA * a) + cfg.kG;
00075     }
00076 
00077     private:
00078 
00079     ff_config_t &cfg;
00080 
00081 };
00082 
00083 
00091 FeedForward::ff_config_t tune_feedforward(vex::motor_group &motor, double pct, double duration);
```

## 6.21 motion_controller.h

```
00001 #pragma once
00002 #include "../core/include/utils/controls/pid.h"
00003 #include "../core/include/utils/controls/feedforward.h"
00004 #include "../core/include/utils/controls/trapezoid_profile.h"
00005 #include "../core/include/utils/controls/feedback_base.h"
00006 #include "../core/include/subsystems/tank_drive.h"
00007 #include "vex.h"
00008 
00025 class MotionController : public Feedback
00026 {
00027     public:
00028 
00034     typedef struct
00035     {
00036         double max_v;
00037         double accel;
00038         PID::pid_config_t pid_cfg;
00039         FeedForward::ff_config_t ff_cfg;
00040     } m_profile_cfg_t;
00041 
00051     MotionController(m_profile_cfg_t &config);
00052 
00057     void init(double start_pt, double end_pt, double start_vel, double end_vel) override;
00058 
00065     double update(double sensor_val) override;
00066 
00070     double get() override;
00071 
00079     void set_limits(double lower, double upper) override;
00080 
00085     bool is_on_target() override;
00086 
00090     motion_t get_motion();
00091 
00110     static FeedForward::ff_config_t tune_feedforward(TankDrive &drive, OdometryTank &odometry, double
      pct=0.6, double duration=2);
00111 
00112     private:
00113 
00114     m_profile_cfg_t config;
00115 
00116     PID pid;
00117     FeedForward ff;
00118     TrapezoidProfile profile;
00119 
00120     double current_pos;
00121     double end_pt;
00122 
00123     double lower_limit = 0, upper_limit = 0;
00124     double out = 0;
00125     motion_t cur_motion;
00126 
00127     vex::timer tmr;
00128 
00129 };
```

## 6.22 pid.h

```
00001 #pragma once
00002 
00003 #include <cmath>
00004 #include "vex.h"
```

```
00005 #include "../core/include/utils/controls/feedback_base.h"
00006
00007 using namespace vex;
00008
00023 class PID : public Feedback
00024 {
00025 public:
00029   enum ERROR_TYPE{
00030     LINEAR,
00031     ANGULAR // assumes degrees
00032   };
00040   struct pid_config_t
00041   {
00042     double p;
00043     double i;
00044     double d;
00045     double deadband;
00046     double on_target_time;
00047     ERROR_TYPE error_method;
00048   };
00049
00050
00051
00056   PID(pid_config_t &config);
00057
00058
00069   void init(double start_pt, double set_pt, double start_vel = 0, double end_vel = 0) override;
00070
00077   double update(double sensor_val) override;
00078
00079
00084   double get_sensor_val();
00085
00086
00091   double get() override;
00092
00099   void set_limits(double lower, double upper) override;
00100
00105   bool is_on_target() override;
00106
00110   void reset();
00111
00116   double get_error();
00117
00122   double get_target();
00123
00128   void set_target(double target);
00129
00130
00131   pid_config_t &config;
00132
00133 private:
00134
00135
00136   double last_error = 0;
00137   double accum_error = 0;
00138
00139   double last_time = 0;
00140   double on_target_last_time = 0;
00141
00142   double lower_limit = 0;
00143   double upper_limit = 0;
00144
00145   double target = 0;
00146   double target_vel = 0;
00147   double sensor_val = 0;
00148   double out = 0;
00149
00150   bool is_checking_on_target = false;
00151
00152   timer pid_timer;
00153 };
```

## 6.23 pidff.h

```
00001 #pragma once
00002 #include "../core/include/utils/controls/feedback_base.h"
00003 #include "../core/include/utils/controls/pid.h"
00004 #include "../core/include/utils/controls/feedforward.h"
00005
00006 class PIDFF : public Feedback
00007 {
00008     public:
```

```
00009
00010     PIDFF(PID::pid_config_t &pid_cfg, FeedForward::ff_config_t &ff_cfg);
00011
00020     void init(double start_pt, double set_pt, double start_vel, double end_vel) override;
00021
00026     void set_target(double set_pt);
00027
00035     double update(double val) override;
00036
00045     double update(double val, double vel_setpt, double a_setpt=0);
00046
00050     double get() override;
00051
00058     void set_limits(double lower, double upper) override;
00059
00063     bool is_on_target() override;
00064
00065     PID pid;
00066
00067
00068     private:
00069
00070     FeedForward::ff_config_t &ff_cfg;
00071
00072     FeedForward ff;
00073
00074     double out;
00075     double lower_lim, upper_lim;
00076
00077 };
```

## 6.24 take_back_half.h

```
00001 #pragma once
00002 #include "../core/include/utils/controls/feedback_base.h"
00003
00006 class TakeBackHalf : public Feedback
00007 {
00008
00009 public:
00010     TakeBackHalf(double TBH_gain, double first_cross_split, double on_target_threshold);
00019     void init(double start_pt, double set_pt, double, double);
00026     double update(double val) override;
00027
00031     double get() override;
00032
00039     void set_limits(double lower, double upper) override;
00040
00044     bool is_on_target() override;
00045
00046     double TBH_gain;
00047     double first_cross_split;
00048 private:
00049     double on_target_threshhold;
00050
00051     double target = 0.0;
00052
00053     bool first_cross = true;
00054     double tbh = 0.0;
00055     double prev_error = 0.0;
00056
00057     double output = 0.0;
00058     double lower = 0.0, upper = 0.0;
00059 };
```

## 6.25 trapezoid_profile.h

```
00001 #pragma once
00002
00003 const int MAX_TRAPEZOID_PROFILE_SEGMENTS = 4;
00004
00008 typedef struct
00009 {
00010     double pos;
00011     double vel;
00012     double accel;
00013
00014 } motion_t;
00015
```

```
00019 typedef struct
00020 {
00021     double pos_after;
00022     double vel_after;
00023     double accel;
00024     double duration;
00025 } trapezoid_profile_segment_t;
00026
00060 class TrapezoidProfile
00061 {
00062     public:
00063
00070     TrapezoidProfile(double max_v, double accel);
00071
00079     motion_t calculate(double time_s, double pos_s);
00080
00087     motion_t calculate_time_based(double time_s);
00088
00095     void set_endpts(double start, double end);
00096
00103     void set_vel_endpts(double start, double end);
00104
00110     void set_accel(double accel);
00111
00117     void set_max_v(double max_v);
00118
00124     double get_movement_time();
00125
00126     private:
00127     double si, sf;
00128     double vi, vf;
00129     double max_v;
00130     double accel;
00131
00132     trapezoid_profile_segment_t segments[MAX_TRAPEZOID_PROFILE_SEGMENTS];
00133     int num_acceleration_phases;
00134
00135     bool precalculated;
00136
00142     bool precalculate();
00143
00152     trapezoid_profile_segment_t calculate_kinetic_motion(double si, double vi, double v_target);
00153
00161     trapezoid_profile_segment_t calculate_next_segment(double s, double v);
00162 };
```

## 6.26 generic_auto.h

```
00001 #pragma once
00002
00003 #include <queue>
00004 #include <map>
00005 #include "vex.h"
00006 #include <functional>
00007
00008 typedef std::function<bool(void)> state_ptr;
00009
00014 class GenericAuto
00015 {
00016   public:
00017
00031   [[deprecated("Use CommandController instead.")]]
00032   bool run(bool blocking);
00033
00038   [[deprecated("Use CommandController instead.")]]
00039   void add(state_ptr new_state);
00040
00045   [[deprecated("Use CommandController instead.")]]
00046   void add_async(state_ptr async_state);
00047
00052   [[deprecated("Use CommandController instead.")]]
00053   void add_delay(int ms);
00054
00055   private:
00056
00057   std::queue<state_ptr> state_list;
00058
00059 };
```

# 6.27 geometry.h

```
00001 #pragma once
00002 #include <cmath>
00003
00007 struct point_t
00008 {
00009     double x;
00010     double y;
00011
00017     double dist(const point_t other) const
00018     {
00019         return std::sqrt(std::pow(this->x - other.x, 2) + pow(this->y - other.y, 2));
00020     }
00021
00027     point_t operator+(const point_t &other) const
00028     {
00029         point_t p{
00030             .x = this->x + other.x,
00031             .y = this->y + other.y};
00032         return p;
00033     }
00034
00040     point_t operator-(const point_t &other) const
00041     {
00042         point_t p{
00043             .x = this->x - other.x,
00044             .y = this->y - other.y};
00045         return p;
00046     }
00047
00048     point_t operator*(double s) const
00049     {
00050         return {x * s, y * s};
00051     }
00052     point_t operator/(double s) const
00053     {
00054         return {x / s, y / s};
00055     }
00056
00057     point_t operator-() const
00058     {
00059         return {-x, -y};
00060     }
00061     point_t operator+() const
00062     {
00063         return {x, y};
00064     }
00065
00066     bool operator==(const point_t &rhs)
00067     {
00068         return x == rhs.x && y == rhs.y;
00069     }
00070 };
00071
00075 struct pose_t
00076 {
00077     double x;
00078     double y;
00079     double rot;
00080
00081     point_t get_point()
00082     {
00083         return point_t{.x = x, .y = y};
00084     }
00085
00086 } ;
00087
00088 struct Rect
00089 {
00090     point_t min;
00091     point_t max;
00092     static Rect from_min_and_size(point_t min, point_t size){
00093         return {min, min+size};
00094     }
00095     point_t dimensions() const
00096     {
00097         return max - min;
00098     }
00099     point_t center() const{
00100         return (min + max)/2;
00101     }
00102     double width() const{
00103         return max.x - min.x;
00104     }
00105     double height() const{
00106         return max.y - min.y;
```

```
00107     }
00108     bool contains(point_t p) const
00109     {
00110         bool xin = p.x > min.x && p.x < max.x;
00111         bool yin = p.y > min.y && p.y < max.y;
00112         return xin && yin;
00113     }
00114
00115 };
00116
00117 struct Mat2
00118 {
00119     double X11, X12;
00120     double X21, X22;
00121     point_t operator*(const point_t p) const
00122     {
00123         double outx = p.x * X11 + p.y * X12;
00124         double outy = p.x * X21 + p.y * X22;
00125         return {outx, outy};
00126     }
00127
00128     static Mat2 FromRotationDegrees(double degrees)
00129     {
00130         double rad = degrees * (M_PI / 180.0);
00131         double c = cos(rad);
00132         double s = sin(rad);
00133         return {c, -s, s, c};
00134     }
00135 };
```

## 6.28 graph_drawer.h

```
00001 #pragma once
00002
00003 #include <string>
00004 #include <stdio.h>
00005 #include <vector>
00006 #include <cmath>
00007 #include "vex.h"
00008 #include "../core/include/utils/geometry.h"
00009 #include "../core/include/utils/vector2d.h"
00010
00011 class GraphDrawer
00012 {
00013 public:
00020   GraphDrawer(int num_samples, double lower_bound, double upper_bound, std::vector<vex::color> colors,
      size_t num_series = 1);
00025   void add_samples(std::vector<point_t> sample);
00026
00031   void add_samples(std::vector<double> sample);
00032
00040   void draw(vex::brain::lcd &screen, int x, int y, int width, int height);
00041
00042 private:
00043   std::vector<std::vector<point_t» series;
00044   int sample_index = 0;
00045   std::vector<vex::color> cols;
00046   vex::color bgcol = vex::transparent;
00047   bool border;
00048   double upper;
00049   double lower;
00050   bool auto_fit = false;
00051 };
```

## 6.29 logger.h

```
00001 #pragma once
00002
00003 #include <cstdarg>
00004 #include <cstdio>
00005 #include <string>
00006 #include "vex.h"
00007
00009 enum LogLevel
00010 {
00011     DEBUG,
00012     NOTICE,
00013     WARNING,
00014     ERROR,
```

```
00015     CRITICAL,
00016     TIME
00017 };
00018
00020 class Logger
00021 {
00022 private:
00023     const std::string filename;
00024     vex::brain::sdcard sd;
00025     void write_level(LogLevel l);
00026
00027 public:
00029     static constexpr int MAX_FORMAT_LEN = 512;
00032     explicit Logger(const std::string &filename);
00033
00035     Logger(const Logger &l) = delete;
00037     Logger &operator=(const Logger &l) = delete;
00038
00039
00042     void Log(const std::string &s);
00043
00047     void Log(LogLevel level, const std::string &s);
00048
00051     void Logln(const std::string &s);
00052
00056     void Logln(LogLevel level, const std::string &s);
00057
00061     void Logf(const char *fmt, ...);
00062
00067     void Logf(LogLevel level, const char *fmt, ...);
00068 };
```

## 6.30 math_util.h

```
00001 #pragma once
00002 #include <vector>
00003 #include "math.h"
00004 #include "vex.h"
00005 #include "../core/include/utils/geometry.h"
00006
00007
00015 double clamp(double value, double low, double high);
00016
00023 double lerp(double a, double b, double t);
00030 double sign(double x);
00031
00032 double wrap_angle_deg(double input);
00033 double wrap_angle_rad(double input);
00034
00035 /*
00036 Calculates the variance of  a set of numbers (needed for linear regression)
00037 https://en.wikipedia.org/wiki/Variance
00038 @param values   the values for which the variance is taken
00039 @param mean     the average of values
00040 */
00041 double variance(std::vector<double> const &values, double mean);
00042
00043
00044 /*
00045 Calculates the average of a vector of doubles
00046 @param values   the list of values for which the average is taken
00047 */
00048 double mean(std::vector<double> const &values);
00049
00050 /*
00051 Calculates the covariance of a set of points (needed for linear regression)
00052 https://en.wikipedia.org/wiki/Covariance
00053
00054 @param points   the points for which the covariance is taken
00055 @param meanx    the mean value of all x coordinates in points
00056 @param meany    the mean value of all y coordinates in points
00057 */
00058 double covariance(std::vector<std::pair<double, double» const &points, double meanx, double meany);
00059
00060 /*
00061 Calculates the slope and y intercept of the line of best fit for the data
00062 @param points the points for the data
00063 */
00064 std::pair<double, double> calculate_linear_regression(std::vector<std::pair<double, double» const
      &points);
00065
00066 double estimate_path_length(const std::vector<point_t> &points);
```

## 6.31 moving_average.h

```
00001 #pragma once
00002 #include <vector>
00003
00008 class Filter
00009 {
00010 public:
00011   virtual void add_entry(double n) = 0;
00012   virtual double get_value() const = 0;
00013 };
00014
00027 class MovingAverage : public Filter
00028 {
00029 public:
00030   /*
00031    * Create a moving average calculator with 0 as the default value
00032    *
00033    * @param buffer_size    The size of the buffer. The number of samples that constitute a valid
      reading
00034    */
00035   MovingAverage(int buffer_size);
00036   /*
00037    * Create a moving average calculator with a specified default value
00038    * @param buffer_size    The size of the buffer. The number of samples that constitute a valid
      reading
00039    * @param starting_value The value that the average will be before any data is added
00040    */
00041   MovingAverage(int buffer_size, double starting_value);
00042
00043   /*
00044    * Add a reading to the buffer
00045    * Before:
00046    * [ 1 1 2 2 3 3] => 2
00047    *   ^
00048    * After:
00049    * [ 2 1 2 2 3 3] => 2.16
00050    *     ^
00051    * @param n  the sample that will be added to the moving average.
00052    */
00053   void add_entry(double n);
00054
00059   double get_value() const;
00060
00065   int get_size() const;
00066
00067 private:
00068   int buffer_index;           // index of the next value to be overridden
00069   std::vector<double> buffer; // all current data readings we've taken
00070   double current_avg;         // the current value of the data
00071 };
00072
00085 class ExponentialMovingAverage : public Filter
00086 {
00087 public:
00088   /*
00089    * Create a moving average calculator with 0 as the default value
00090    *
00091    * @param buffer_size    The size of the buffer. The number of samples that constitute a valid
      reading
00092    */
00093   ExponentialMovingAverage(int buffer_size);
00094   /*
00095    * Create a moving average calculator with a specified default value
00096    * @param buffer_size    The size of the buffer. The number of samples that constitute a valid
      reading
00097    * @param starting_value The value that the average will be before any data is added
00098    */
00099   ExponentialMovingAverage(int buffer_size, double starting_value);
00100
00101   /*
00102    * Add a reading to the buffer
00103    * Before:
00104    * [ 1 1 2 2 3 3] => 2
00105    *   ^
00106    * After:
00107    * [ 2 1 2 2 3 3] => 2.16
00108    *     ^
00109    * @param n  the sample that will be added to the moving average.
00110    */
00111   void add_entry(double n);
00112
00117   double get_value();
00118
00123   int get_size();
00124
00125 private:
```

```
00126   int buffer_index;           // index of the next value to be overridden
00127   std::vector<double> buffer; // all current data readings we've taken
00128   double current_avg;         // the current value of the data
00129 };
```

## 6.32 pure_pursuit.h

```
00001 #pragma once
00002
00003 #include <vector>
00004 #include "../core/include/utils/geometry.h"
00005 #include "../core/include/utils/vector2d.h"
00006 #include "vex.h"
00007
00008 using namespace vex;
00009
00010 namespace PurePursuit {
00014   class Path
00015   {
00016     public:
00022       Path(std::vector<point_t> points, double radius);
00023
00027       std::vector<point_t> get_points();
00028
00032       double get_radius();
00033
00037       bool is_valid();
00038
00039     private:
00040       std::vector<point_t> points;
00041       double radius;
00042       bool valid;
00043   };
00048   struct spline
00049   {
00050     double a, b, c, d, x_start, x_end;
00051
00052     double getY(double x) {
00053       return a * pow((x - x_start), 3) + b * pow((x - x_start), 2) + c * (x - x_start) + d;
00054     }
00055   };
00060   struct hermite_point
00061   {
00062     double x;
00063     double y;
00064     double dir;
00065     double mag;
00066
00067     point_t getPoint() const {
00068       return {x, y};
00069     }
00070
00071     Vector2D getTangent() const {
00072       return Vector2D(dir, mag);
00073     }
00074   };
00075
00080   extern std::vector<point_t> line_circle_intersections(point_t center, double r, point_t point1,
      point_t point2);
00084   extern point_t get_lookahead(const std::vector<point_t> &path, pose_t robot_loc, double radius);
00085
00089   extern std::vector<point_t> inject_path(const std::vector<point_t> &path, double spacing);
00090
00102   extern std::vector<point_t> smooth_path(const std::vector<point_t> &path, double weight_data, double
      weight_smooth, double tolerance);
00103
00104   extern std::vector<point_t> smooth_path_cubic(const std::vector<point_t> &path, double res);
00105
00114   extern std::vector<point_t> smooth_path_hermite(const std::vector<hermite_point> &path, double
      step);
00115
00126   extern double estimate_remaining_dist(const std::vector<point_t> &path, pose_t robot_pose, double
      radius);
00127
00128 }
```

## 6.33 serializer.h

```
00001 #pragma once
```

```
00002 #include <algorithm>
00003 #include <map>
00004 #include <string>
00005 #include <vector>
00006 #include <stdio.h>
00007 #include <vex.h>
00008
00010 const char serialization_separator = '$';
00012 const std::size_t MAX_FILE_SIZE = 4096;
00013
00015 class Serializer
00016 {
00017 private:
00018     bool flush_always;
00019     std::string filename;
00020     std::map<std::string, int> ints;
00021     std::map<std::string, bool> bools;
00022     std::map<std::string, double> doubles;
00023     std::map<std::string, std::string> strings;
00024
00026     bool read_from_disk();
00027
00028 public:
00030     ~Serializer()
00031     {
00032         save_to_disk();
00033         printf("Saving %s\n", filename.c_str());
00034         fflush(stdout);
00035     }
00036
00040     explicit Serializer(const std::string &filename, bool flush_always = true) :
    flush_always(flush_always), filename(filename), ints({}), bools({}), doubles({}), strings({})
00041
00042     {
00043         read_from_disk();
00044     }
00045
00047     void save_to_disk() const;
00048
00050
00054     void set_int(const std::string &name, int i);
00055
00059     void set_bool(const std::string &name, bool b);
00060
00064     void set_double(const std::string &name, double d);
00065
00069     void set_string(const std::string &name, std::string str);
00070
00073
00078     int int_or(const std::string &name, int otherwise);
00079
00084     bool bool_or(const std::string &name, bool otherwise);
00085
00090     double double_or(const std::string &name, double otherwise);
00091
00096     std::string string_or(const std::string &name, std::string otherwise);
00097 };
```

## 6.34 vector2d.h

```
00001 #pragma once
00002
00003
00004 #include <cmath>
00005 #include "../core/include/utils/geometry.h"
00006
00007 #ifndef PI
00008 #define PI 3.141592654
00009 #endif
00015 class Vector2D
00016 {
00017 public:
00024     Vector2D(double dir, double mag);
00025
00031     Vector2D(point_t p);
00032
00040     double get_dir() const;
00041
00045     double get_mag() const;
00046
00050     double get_x() const;
00051
00055     double get_y() const;
```

```
00056
00061     Vector2D normalize();
00062
00067     point_t point();
00068
00074     Vector2D operator*(const double &x);
00081     Vector2D operator+(const Vector2D &other);
00088     Vector2D operator-(const Vector2D &other);
00089
00090 private:
00091
00092     double dir, mag;
00093
00094 };
00095
00101 double deg2rad(double deg);
00102
00109 double rad2deg(double r);
```

# Index