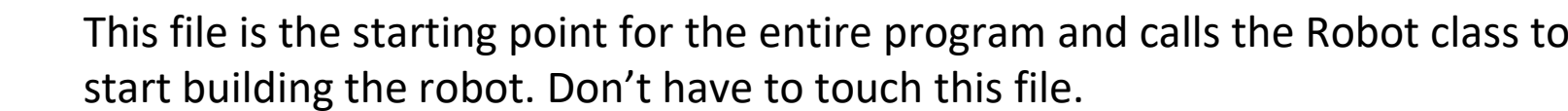


Main.java



This file defines the Robot class and its purpose is to maintain the overall state of the robot. It is implemented as a State Machine that represents the state of the robot at various points in time. Initialize the robot structure. Starts the command scheduler.

It is singleton

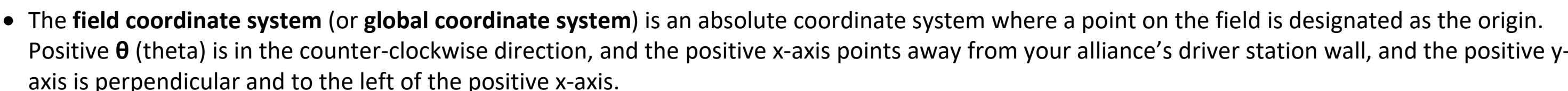
It is generally recommended to call it from the `robotPeriodic()` method of the `Robot` class

Handles autonomous and periodic loops

The main structure of the robot is built in this file.
It defines Subsystems and their Default Commands.
It sets up Autonomous Commands that are run during the Autonomous mode of the competition.
It is also where mappings between the Joystick and various Commands are defined.

This file provides a central location for defining constants. Constants are values assigned to variables that do not change throughout the execution of the program.

Field Coordination System (Absolute)



- The **robot coordinate system** (or **local coordinate system**) is a relative coordinate system where the robot is the origin. The direction the robot is facing is the positive x axis, and the positive y axis is perpendicular, to the left of the robot. Positive
 - is counter-clockwise.
 - **Your robot is in red alliance.**
- Joystick forward -Y

It moves robot away from Main driver. It should drive the robot BACKWARDS. To make the robot forward we need to invert the joystick control.
- Joystick backward +Y

It moves robot towards Main driver. It should drive the robot FORWARDS. To make the robot backward we need to invert the joystick control.
- Joystick left -X

It drives the robot main driver's right. To make the robot turn the main driver's left we need to invert the joystick control.
- Joystick right +X

It drives the robot main driver's left. To make the robot turn the main driver's right we need to invert the joystick control.

Field Coordination System (Absolute)

