**Okapi Notes**

**Motor.cpp**

Function doesn’t exist (or renamed):

* Motor\_set\_pos\_pid
  + Affected functions: setPosPID()
* Motor\_convert\_pid
  + Affected functions: setPosPID() , setVelPID()
* Motor\_set\_pos\_pid\_full
  + Affected functions: setPosPIDFull()
* Motor\_convert\_pid\_full
  + Affected functions: setPosPIDFull(), setVelPIDFull()
* Motor\_set\_vel\_pid
  + Affected functions: setVelPID()
* Motor\_set\_vel\_pid\_full
  + Affected functions: setVelPIDFull()

Changes:

* setPosPID()
  + Now calls for additional argument “motor” of type pros::motor\_pid\_s\_t. Function instead now checks if the motor exists, and if so sets argument values for given motor’s PID values
* setPosPIDFull()
  + Now calls for additional argument “motor” of type pros::motor\_pid\_full\_s\_t. Function instead now checks if the motor exists, and if so sets argument values for given motor’s PID values
* setVelPID()
  + Deprecated, found note in previous PROS version that Vex doesn’t allow this anymore and could damage motor
* setVelPIDFull()
  + Deprecated, same reason as above

**NOT\_INITIALIZE\_TASK**

* This macro contains the function strcmp, which compiler doesn’t recognize (probably just need to “#include <cstring>”). Files that needed this are coreProsApi.hpp and chassisControllerBuilder.cpp.

Changes:

* Confirmed the strcmp() function to be part of the cstring library (<https://cplusplus.com/reference/cstring/strcmp/>). Added ‘#include <cstring>’ to both coreProsAPI.hpp and chassisControllerBuilder.cpp

**IMU.cpp**

Undefined typedefs:

* Imu\_accel\_s\_t
  + Affected functions: getAcceleration()
* Euler\_s\_t
  + Affected functions: readAngle()
* E\_IMU\_STATUS\_CALIBRATING undefined.
  + Affected functions: isCalibrating()

Changes:

* getAcceleration()
  + Changed pros::c::imu\_accel\_s\_t to pros::imu\_accel\_s\_t and changed pros::c::imu\_get\_accel to pros::get\_accel. Now returns the associated double from the imu\_raw\_s object depending on the axis case statement
* readAngle()
  + Now uses the input port number argument used to initialize the IMU and sends that into pros::c::get\_pitch, pros::c::get\_yaw, or pros::c::get\_roll depending on which axes
* isCalibrating()
  + Now uses pros::is\_calibrating()