Phoenix Framework

The software framework for all CTR-Electronics robot components.

See what control components make sense for your robotic needs at CTR-Electronics.

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Hardware setup

Text here.

Motor Controllers

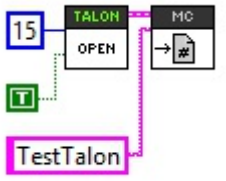
CTRE provides two CAN/PWM motor controller options...

- Victor SPX
- Talon SRX

Where to begin? Create the object.

The first step of controlling a motor controller is to instantiate the controller in your robot controller software.

If using LabVIEW, use the Open VI corresponding to your motor controller. Here we are creating an object for the Talon with device ID 15.



If using a programming language, create a TalonSRX object using the appropriate class name. `private TalonSRX m_Wheel = new TalonSRX(15);`

Regardless of the what the motor controller is used for, the next step is usually open-loop (no sensor) control. This is to ensure the mechanism is functional and that the motor and motor controller is wired correctly.

Start with the open-loop features below and configure each setting that is applicable.

Open-Loop (No Sensor) Control

These features and configurations influence the behavior of the motor controller when it is directly controlled by the robot controller.

Pick your direction

The

Pick your neutral mode

Text here.

Current limiting

Text here.

Ramping

Text here.

Follower

Text here.