Revision 3.04 2/11/2023 – Added new pose est2

This documents which Java/C++ WPILIB routines have been duplicated in LabVIEW, and which ones are not needed (for example because all that is needed is a cluster unpack function), and what isn't done....yet...

VI / CTL Totals
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Doc completed Pct 97.19% Optimization Pct 57.82%

Optimize legend: S = Subroutine, I = Inline, X = reviewed, nothing done. (In some cases, after sufficient debug and use, additional optimizations could be considered.)

'===== BASE

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ANALOG DELAY	X Implemented	X Documented X Not Well IR		X Menu item	eu.		VI Name AnalogDelay_Execute.vi	Function Prototype	Notes Similar to interpolated tree map	Code Review	Test Program	Error Checking
BUMPLESS TRANSFER	X Implemented	X Documented X Not With IR		X Menu Item	Test Routine		VI Name BumplessTransfer Execute.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
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FUNCTION GENERATOR	X	X		X			FunctionGenerator_Add_Value.vi FunctionGenerator_Add_XY.vi FunctionGenerator_Calculate.vi		Similar to interpolated tree map Similar to interpolated tree map Similar to interpolated tree map			
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FUNCTION GENERATOR MATRIX	X	X X X Documented	\ \ \ \ \ \ \ \ \ \ \ \ \ \ \ \ \ \ \	X X X Menu Item N X X Menu Item N I Execution Optimized	Test Routil		VI Name FunctionGeneratorMatrix_Add.vi FunctionGeneratorMatrix_Calculate.vi FunctionGeneratorMatrix_New.vi	Function Prototype	Notes Similar to interpolated tree map Similar to interpolated tree map Similar to interpolated tree map	Code Review	Test Program	Error Checking

Revision 3.04 2/11/2023 – Added new pose est2 Routine Test Function Prototype VI Name Notes LEAD LAG X X X X I LeadLag Execute.vi Routine VI Name Function Prototype Notes LINEAR FILTER X LinearFilter BackwardFiniteDifference.vi X I X X X X X SI X X X X X X X X X X I LinearFilter Calculate.vi LinearFilter\_CutoffFrequency.vi X LinearFilter\_Execute.vi Labview style helper AN INTERNAL ROUTINE XX No I LinearFilter Factorial.vi LinearFilter FiniteDifference.vi XX X I X X LinearFilter HighPass.vi Χ X X X X X X X X LinearFilter HighPassBW1.vi LinearFilter\_HighPassBW2.vi X X X X LinearFilter LowPassBW1.vi X X X X LinearFilter LowPassBW2.vi X X X X LinearFilter\_MovingAverage.vi Χ LinearFilter New.vi LinearFilter Reset.vi LinearFilter\_ResetToValue.vi XX X LinearFilter SinglePoleIIR.vi LinearFilter TimeConst.vi  $X \mid X \mid X \mid X$ VI Name Function Prototype Notes MEDIAN FILTER X X X MedianFilter Calculate.vi X X X X MedianFilter\_Execute.vi Labview style helper XX X SI MedianFilter New.vi X SI MedianFilter Reset.vi X X X X SI MedianFilter ResetToValue.vi VI Name Function Prototype Notes SLEW RATE FILTER X X SlewRateLimiter Calculate.vi X XX X SI SlewRateLimiter\_Close.vi X X X X I X SlewRateLimiter Execute.vi Labview style helper X X X X SI SlewRateLimiter GetRate.vi SlewRateLimiter\_New.vi XX Χ XX Χ SlewRateLimiter NewInitialZero.vi X X X X X I X SI SlewRateLimiter Reset.vi Х

Page 2 / 40 FRC\_LabVIEW\_Trajectory\_Library\_Routines.xlsx

SlewRateLimiter\_SetRate.vi

1/2023 – Added new pose est2						_				_				
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		X .	X	X	Χ				Timer GetAndReset.vi					
		X .	X	Χ	Νο				Timer_GetInternal.vi		Internal (private) only			
		X .	X		Χ				Timer_HasPeriodPassed.vi					
		X .		X					Timer_HasPeriodPassedOnce.vi					
		X . X .	<u>x</u>		X			X	Timer_New.vi Timer Reset.vi			+		
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	_	X . X .	X	X	Χ	SI			TimeInterpBoolean_GetNewestSample.vi					
		X .	X	X	Х	I			TimeInterpBoolean_GetSample.vi			$\longrightarrow$		
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		<i>X</i> .	X	X	X	SI			TimeInterpPose2d_Clear.vi					
		X .	X X	<i>X</i>	X	SI	-		TimeInterpPose2d_GetNewestSample.vi TimeInterpPose2d_GetSample.vi		+			
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TIME INTERPOLATABLE ROTATION2D	X	X X	( X	1			TimeInterpRotation2d_AddSample.vi		Update to use create matrix				Х
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							TimeInterpRotation2d_GetTimeForValue.vi						Х
	X	X X	( X	SI			TimeInterpRotation2d_New.vi						Х
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	7.	,,	, ,,				TimeInterpVariant_GetTimeForValue.vi						X
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DEBOUNCER	Χ	X	X		Debouncer_New.vi			
	Χ	Χ	X		Debouncer_Calculate.vi			
	Χ	Χ	XX		Debouncer_Execute.vi			
	Χ	X	No		Debouncer_Reset.vi			
	Χ	Χ	No		Debouncer_HasElapsed.vi			

'======= CONTROLLER

ARM FF	X X X	X X X X	X		X X Menu Item	Execution Optimized	Test Routine		ArmFF_Calculate.vi ArmFF_CalculateVelocityOnly.vi ArmFF_Execute.vi ArmFF_ExecuteVelocityOnly.vi ArmFF_MaxAchieveAccel.vi ArmFF_MaxAchieveVelocity.vi ArmFF_MinAchieveAccel.vi		Notes  LabVIEW style single call  LabVIEW style single call	Code Review	Test Program	Error Checking
	X	X			X X				ArmFF_MinAchieveVelocity.vi ArmFF_New_ZeroGravity.vi					
	X				X				ArmFF_New.vi					
BANG BANG	X X X X X X X X X X X X X X X X X X X	X X X X X X	X	(	X X X X X X X X X X X X X X X X X X X	의 의 의 의 의 의 의 의 의 의 의 의 의 의 의 의 의 의 의	Test Routine		VI Name  BangBang_AtSetpoint.vi BangBang_Calculate_PV.vi BangBang_Calculate_SP_PV.vi BangBang_Execute.vi BangBang_GetAll.vi BangBang_GetError.vi BangBang_New.vi BangBang_SetSetpoint.vi BangBang_SetTolerance.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
CONTROLLER UTIL	X  mplemented				X Menu Item	Secution Optimized	Test Routine	Sample Program	VI Name ControllerUtil_GetModulusError.vi		Notes This was short lived in WPILIB, but still useful here.	Code Review	Test Program	Error Checking
ELEV FF	X   Implemented	X	X		X Menu Item	Execution Optimized	Test Routine		VI Name  ElevFF_Calculate.vi  ElevFF_CalculateVelocityOnly.vi  ElevFF_Execute.vi  ElevFF_ExecuteVelocityOnly.vi  ElevFF MaxAchieveAccel.vi	Function Prototype	Notes  LabVIEW style single call  LabVIEW style single call	Code Review	Test Program	Error Checking

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	Χ	X		Χ				ElevFF_MaxAchieveVelocity.vi					
	X	X		X				ElevFF_MinAchieveAccel.vi					
	X	X		X				ElevFF_MinAchieveVelocity.vi ElevFF New ZeroAccel.vi					
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HOL_DRV_CTRL	. X	$\overline{X}$	X	X				HolDrvCtrl AdvCalculate Trajectory.vi		Added 1/24/2022		•	
	X	Χ	Χ	Χ				HolDrvCtrl_AdvCalculate.vi		Added 1/24/2022			
	X	Χ		Χ	SI			HolDrvCtrl_AtReference.vi		Added 1/26/21			
	Χ	Χ		Χ	I			HolDrvCtrl_Calculate_Trajectory.vi		Added 1/26/21			
	X	X		X	I			HolDrvCtrl_Calculate.vi		Added 1/26/21			
	X	X	X	X				HolDrvCtrl_Execute_Trajectory.vi		Added 1/24/2022			
	X	X	Χ	X	SI			HolDrvCtrl_Execute.vi HolDrvCtrl New.vi		Future Added 1/26/21			
	X	X	Χ	X	SI			HolDrvCtrl_PackExecuteSP.vi		MUGU 1/20/21			
	X	X	X	X	J.			HolDrvCtrl PackPID.vi		Added 1/24/2022			
	X	X	X	X				HolDrvCtrl PackProfPID.vi		Added 1/24/2022			
	Χ	Χ		Χ	SI			HolDrvCtrl_SetEnabled.vi		Added 1/26/21			
	Χ	Χ		Χ	SI			HolDrvCtrl_SetTolerance.vi		Added 1/26/21			
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program				Code Review	st Program	or Checking
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PID AUTOTUNE	Χ	X	Χ	No				PIDAutoTune_ClosedLoopStep.vi					
	X	X	X	No				PIDAutoTune_Convert_Academic_To_NonInteracting.vi					
	X	X	X	No X				PIDAutoTune_OpenLoopStep.vi PIDAutoTune_SetTuningArguments.vi					
	X	X	X	X				PIDAutoTune Step Execute.vi					
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PID CONTROLLER	$\mathbb{R}^{\mathbb{R}}$	$\overline{X}$	X	X				PIDController AdvCalculate FF Sp Pv Per.vi	Tunction Flototype	Advanced PID	0		Ē
	X	X	Χ	Χ				PIDController_AdvCalculate_FF_Sp_Pv.vi		Advanced PID			
	X	X	Χ	X			X	PIDController_AdvExecute.vi		Labview style helper. Advanced			
	~			_	01			PIDController AtSetpoint.vi		PID			
	X	X		X	SI			PIDController_AtSetpoint.vi PIDController Calculate PV.vi					
	X	X		X				PIDController Calculate SP PV.vi		+			
	X	X		X	SI			PIDController_DisableContinousInput.vi					
	X	X		X	SI			PIDController EnableContinousInput.vi					
	Χ	Χ	Χ	Χ			Χ	PIDController_Execute.vi		Labview style helper			
								PIDController_GetContinuousError.vi		OBSOLETE – Removed			
	X	X		X	SI			PIDController_GetPeriod.vi					
	X	X		X	SI			PIDController_GetPID.vi					
	X	X		X	SI			PIDController_GetPositionError.vi					
	X	X		X	SI SI			PIDController_GetSetpoint.vi PIDController GetTolerance.vi					
	X	X		X	SI			PIDController_GetVelocityError.vi					
		X		X	SI			PIDController_IsContinuousInputEnabled.vi					
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	X X X	X		X	1 1			PIDController_New.vi PIDController_NewPeriod.vi					
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	X	X	X X X	X X X	I I SI			PIDController_New.vi PIDController_NewPeriod.vi					

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		X	Χ	Х	SI	I		PIDController Pack InputLimits.vi					
	X	X	$\overline{X}$	X	SI			PIDController Pack Tuning.vi					
	X	X		X	SI			PIDController_Reset.vi					
	Χ	X		X	SI			PIDController_SetD.vi					
		Χ		X				PIDController_SetDerivativeFilter.vi		Advanced PID			
	X	Χ	X	No				PIDController_SetFeedForward_OBSOLETE_DELETE.vi		Advanced PID, Obsolete –			
						+	+	DIDO A III O IEEO : ODOOLETE DELETE :		DELETE			
	X	X	Х	NO				PIDController_SetFFGain_OBSOLETE_DELETE.vi		Advanced PID, Obsolete – DELETE			
	Х	Х		Х	SI			PIDController Setl.vi		DELETE			
	, ·	,		,	Ů,			PIDController_SetInputRange.vi		OBSOLETE - Removed			
	Χ	Χ		Х	SI			PIDController_SetIntegratorRange.vi					
	X	Х	Χ	X	SI			PIDController SetOutputLimits.vi		Advanced PID			
	X	X		X				PIDController_SetP.vi					
	X	Χ	Χ	Χ	SI			PIDController_SetPeriod.vi					
	X	X		X	SI			PIDController_SetPID.vi					
	X	Χ	Χ	X				PIDController_SetPIDF.vi		Advanced PID			
	X	Χ		X				PIDController_SetSetpoint.vi					
	X	Χ		X	SI			PIDController_SetTolerance.vi					
	X	Χ		Χ	SI			PIDController_SetTolerancePandV.vi					
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ID CONTROLLER	X	X		X	SI		0)	ProfiledPIDController AtGoal.vi				.~	<u> </u>
	X	X		X			+	ProfiledPIDController AtSetpoint.vi					
	X	$\hat{x}$		X	<u>J.</u>			ProfiledPIDController Calculate Meas Goal.vi					
	X	X		X			1	ProfiledPIDController Calculate Meas StateGoal TrapCnsrt.vi					
	X	X		X				ProfiledPIDController Calculate Meas StateGoal.vi					
	X	X		X				ProfiledPIDController Calculate Meas.vi					
	X	X		X	SI			ProfiledPIDController DisableContInput.vi					
	X	X		X	SI			ProfiledPIDController_EnableContInput.vi					
	X	Х	X	Х	I			ProfiledPIDController_Execute.vi		Single call LabVIEW style function.			
	X	X		X				ProfiledPIDController_GetGoal.vi					
	X	X		X	SI			ProfiledPIDController_GetPeriod.vi		W/DILID I			
	X	X	Χ	X				ProfiledPIDController_GetPID.vi		WPILIB has separate getters.			
	X	X		X				ProfiledPIDController_GetPositionError.vi					
	X	X		X	SI			ProfiledPIDController_GetSetpoint.vi					
	X	X		X	SI	+	_	ProfiledPIDController_GetTolerance.vi					
	X	X X		X	SI	+	+	ProfiledPIDController_GetVelocityError.vi ProfiledPIDController New.vi					
		$\hat{x}$			1	+	+	ProfiledPIDController_NewPeriod.vi					
	X	X		X	SI			ProfiledPIDController Reset PosOnly.vi					
	X	$\hat{x}$		X	SI		+	ProfiledPIDController_Reset_FosOrity.vi					
U. Caracteristic Control of the Cont		X		X				ProfiledPIDController Reset.vi					
	X	X		X	SI			ProfiledPIDController SetConstraints.vi					
		X		X	SI			ProfiledPIDController SetGoal PosOnly.vi					
	_ ^ I	X		X				ProfiledPIDController SetGoal.vi					
	X							ProfiledPIDController_SetIntegratorRange.vi					
	X	X		Χ	SI		- 1	ProfiledPIDController_SetPID.vi					
	X X X	X		X	SI								
	X X X	Χ		X X X	SI SI			ProfiledPIDController_SetTolerance_PosOnly.vi ProfiledPIDController SetTolerance PosVel.vi					

3.04 2/11/2023 – Added new pose est2	XX	XX	(		Ramsete_Execute_ENG.vi	Use this one!!				
	XX	XX	( SI		Ramsete_Execute_PackTuning_ENG.vi					
	XX	X X	í SI		Ramsete_Execute_PackTuning.vi					
	XX	X X	( )		Ramsete_Execute.vi					
	XX	X	( SI		Ramsete_New_B_Z.vi	new(b, zeta)				
	XX		( SI		Ramsete_New.vi	new				
	XX	X	( SI		Ramsete_SetEnabled.vi	SetEnabled				
	XX	X	( SI		Ramsete_SetTolerance.vi	SetTolerance				
	XX		X		Ramsete_SINC.vi	sinc	internal			
	olemented cumented	Not WPILIB Menu Item	ecution Optimize	st Routine mple Program				de Review	st Program	or Checkina
	lw O		ЙI	Test. Samp	VI Name	Function Prototype	Notes	ပိ	7e	En
SIMPLE MOTOR FEEDFOR	WARD X X	XX	( SI		SimpleMotorFF_Calculate_CalcAccel.vi					
	XX		(		SimpleMotorFF_Calculate_NextV_Dt.vi					
	XX		( SI		SimpleMotorFF_Calculate.vi	public double calculate(double velocity, double acceleration)				
	XX		( SI		SimpleMotorFF_CalculateVelocityOnly.vi	public double calculate(double velocity)				
		XX			SimpleMotorFF_Ka_AutoTune.vi					
	XX	X			SimpleMotorFF_MaxAchieveAccel.vi	public double maxAchievableAcceleration(double maxVoltage,				
	XX	X	. X		SimpleMotorFF_MaxAchieveVel.vi	double velocity)  public double maxAchievableVelocity(double maxVoltage, double acceleration)	•			
	X X	X	( X		SimpleMotorFF_MinAchieveAccel.vi	public double minAchievableAcceleration(double maxVoltage, double velocity)				
	X X	X			SimpleMotorFF_MinAchieveVel.vi	public double minAchievableVelocity(double maxVoltage, double acceleration)				
			( SI		SimpleMotorFF_New.vi	public SimpleMotorFeedforward(double ks, double kv, double ka)				
	XX									
:==== :DV	X X X				SimpleMotorFF_Pack_Ka_Tune_Params.vi	public SimpleMotorFeedforward(double ks, double kv)				
:==== TRY :=====					SimpleMotorFF_Pack_Ka_Tune_Params.vi	public SimpleMotorFeedforward(double ks, double kv)				
TRY :====		X X X X X X X X X X X X X X X X X X X	Execution Optimized	Test Routine Sample Program	VI Name  CoordAxis_D.vi  CoordAxis_E.vi  CoordAxis_N.vi  CoordAxis_N.vi  CoordAxis_S.vi  CoordAxis_S.vi  CoordAxis_U.vi  CoordAxis_U.vi  CoordAxis_W.vi	public SimpleMotorFeedforward(double ks, double kv)  Function Prototype	Notes	Code Review	Test Program	Error Checking
TRY :====	E AXIS X X Will be mented X X X X X X X X X X X X X X X X X X X	Not WPILIB  X  X  X  X  X  X  X  X  X  X  X  X  X	Signature of the secution of the security of t	X Test Routine Sample Program Sample Program	VI Name  CoordAxis_D.vi CoordAxis_E.vi CoordAxis_N.vi CoordAxis_New.vi CoordAxis_S.vi CoordAxis_U.vi CoordAxis_U.vi CoordAxis_W.vi  VI Name  CoordSystem_Convert_Pose3d.vi CoordSystem_Convert_Rotation3d.vi CoordSystem_Convert_Translation3d.vi CoordSystem_Convert_Translation3d.vi			Code Review Code Review	Test Program	Error Checking
TRY	STEM X X X X X X X X X X X X X X X X X X X	Not WPILIB  X  X  X  X  X  X  X  X  X  X  X  X  X	Signature of the state of the s	X X Test Routine Sample Program Sample Program	VI Name  CoordAxis_D.vi CoordAxis_E.vi CoordAxis_N.vi CoordAxis_New.vi CoordAxis_S.vi CoordAxis_U.vi CoordAxis_U.vi CoordAxis_W.vi  VI Name  CoordSystem_Convert_Pose3d.vi CoordSystem_Convert_Rotation3d.vi CoordSystem_Convert_Translation3d.vi CoordSystem_Convert_Transform3d.vi CoordSystem_EDN.vi	Function Prototype	Notes	Review	Test Program	Error Checking
TRY	E AXIS X X Will be mented X X X X X X X X X X X X X X X X X X X	Not WPILIB  Not WPILIB  X  X  X  X  X  X  X  X  X  X  X  X  X	Signature of the secution of the security of t	X X X Test Routine Sample Program	VI Name  CoordAxis_D.vi CoordAxis_E.vi CoordAxis_N.vi CoordAxis_New.vi CoordAxis_S.vi CoordAxis_U.vi CoordAxis_U.vi CoordAxis_W.vi  VI Name  CoordSystem_Convert_Pose3d.vi CoordSystem_Convert_Rotation3d.vi CoordSystem_Convert_Translation3d.vi CoordSystem_Convert_Translation3d.vi	Function Prototype	Notes	Review	Test Program	Error Checking

est2					_				-				
	Implemented	Documented		Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
POSE2D	Χ	X		X	SI			Pose2d_Div.VI					
	Χ	Χ		X	SI			Pose2d_Equals.VI	boolean equals( other obj )				
	Χ	Χ		Χ	X			Pose2d_Exp.vi	pose2d exp( twist2d twist )				
	Χ	X		X	SI			Pose2d_getRotation.vi	rotation2d getRotation()	can also use cluster unpack			
	X	X		X	SI			Pose2d_getTranslation.vi	translation2d getTranslation()	can also use cluster unpack			
	X	X X	Υ _		SI			Pose2d_getXY.vi					
	X	<i>X X</i>	Υ	X .	SI			Pose2d_getXYAngle.vi					
	X	X			I X			Pose2d_Interpolate.vi Pose2d_Log.vi	twist2d log( pose2d end )				
	$\hat{X}$	X		X	SI			Pose2d Minus.vi	transform2d minus( pose2d other )				
	X	X		X	SI			Pose2d_New_TRRO.vi	pose2d new( translation2d, rotation2d )				
	X	X			SI			Pose2d New.vi	pose2d new( double x, double y, rotation2d )				
	X	X			SI			Pose2d Plus.vi	pose2d plus( transform2d other )				
	Χ	X		X	SI			Pose2d RelativeTo.vi	pose2d relativeto( pose2d other )				
	Χ	Χ		X	SI			Pose2d_Times.vi					
	Χ	Χ		X .	SI			Pose2d_TransformBy.vi	pose2d transformby( transform2d other )				
									pose2d new( )	can use cluster constant			
	Implemented	Documented Not Man 15	i wrillb		Execution Optimized	Test Routine	Sample Program				Code Review	st Program	or Checking
	鱼	9	5	₩ I	й	é	Sa	VI Name	Function Prototype	Notes	ပိ	ě	Error
POSE3D	Χ	Χ		$X \mid \cdot$	SI			Pose3d_Div.vi					
	Χ	X			SI			Pose3d_Equals.VI					
	Χ	X		Χ	Χ			Pose3d_Exp.vi					
	X	X		X	SI			Pose3d_getRotation.vi					
	X	X		X	SI			Pose3d_getTranslation.vi					
	X	X	<b>x</b>	X .	SI			Pose3d_getXYZ.vi					
	X	X			<i>I</i>			Pose3d_Interpolate.vi Pose3d_Log.vi			-		
	X	X		X	X SI			Pose3d Minus.vi					
	X	X			SI			Pose3d New.vi					
	X	X		X	SI			Pose3d New Default.vi					
	Х	X			SI			Pose3d New Pose2d.vi					
	Χ	X		X	SI			Pose3d_New_Trans3dRot3d.vi					
	Χ	Χ		X .	SI			Pose3d_Plus.vi					
	X	X		X	SI			Pose3d_RelativeTo.vi					
	X	X		No .	SI			Pose3d_RotationVectorToMatrix.vi					
	X	X			SI SI			Pose3d_ToPose2d.vi					
	X	X		X .	SI			Pose3d_Times.vi Pose3d_TransformBy.vi					
	^	^		^	3,			1 03e3u_mansiomiby.vi					
	Implemented	Documented	OI WYILIB		Execution Optimized	Test Routine	Sample Program				Code Review	est Program	Error Checking
				Ž		7e	လို	VI Name	Function Prototype	Notes	ٽ_	76	Ē
QUATERNION	X	X	_	X	SI			Quaternion_Equals.vi					
	X	X			SI			Quaternion_Get_All.vi					
	X	X		X X	SI SI			Quaternion_Get_LVQuat.vi Quaternion_Get_Vect.vi					
	X	X		X	SI			Quaternion_Get_Vect.vi Quaternion_Get_W.vi			+		
	X	X		X	SI			Quaternion Inverse.vi					
	X	X		X	SI			Quaternion New.vi					
	X	X			SI			Quaternion_New_Default.vi					
	X	X		X	SI			Quaternion_New_LVQuat.vi					
	Χ	X		X .	SI			Quaternion_Normalize.vi					

X		X	X	SI		Quaternion_Plus.vi
X	-   '	X	Χ	SI		Quaternion_Times.vi
X		X	Χ	SI		Quaternion ToRotationVector.vi

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
ROTATION2D	Χ	Χ		Χ	SI	Rotation2d_CreateAngle.vi	rotation2d new( double value )				
	Χ	X		Χ	SI	Rotation2d_CreateAngleDegrees.vi	rotation2d fromDegrees( double degrees )	convert to radians then create			
	Χ	X		Χ	SI	Rotation2d_CreateAngleRotations.vi					
	Χ	X		Χ	SI	Rotation2d_CreateXY.vi	rotation2d new( double x, double y )				
	Χ	X		Χ	SI	Rotation2d_Div.vi					
	Χ	Χ		Χ	SI	Rotation2d_Equals.vi	boolean equals( rotation2d other )				
	Χ	X	X	Χ	SI	Rotation2d_GetAngleCosSin.vi		New 1/26/21			
	Χ	Χ		Χ	SI	Rotation2d_GetCos.VI	double getCos()	use cluster unpack			1
	X	X		X	SI	Rotation2d_GetDegrees.VI	double getDegrees()	use cluster unpack, then convert to degree			
	Χ	X		X	SI	Rotation2d_GetRadians.VI	double getRadians()	use cluster unpack			1
	Χ	X		Χ	SI	Rotation2d_GetRotations.vi					1
	Χ	Χ		Χ	SI	Rotation2d_GetSin.VI	double getSin()	use cluster unpack			1
	Χ	Χ		Χ	SI	Rotation2d_GetTan.VI	double getTan()	can calculate			1
	Χ	X		Χ	SI	Rotation2d_Interpolate.vi					
	Χ	X		Χ	SI	Rotation2d_Minus.vi	rotation2d minus( rotation2d other )				
	Χ	Χ		Χ	SI	Rotation2d_Plus.vi	rotation2d plus( rotation2d other )				
	Χ	X		Χ	SI	Rotation2d_RotateBy.vi	rotation2d rotateby( rotation2d other )				
	Χ	X		Χ	SI	Rotation2d_Times.vi	rotation2d times( double scalar )				
	Χ	Χ		Χ	SI	Rotation2d_UnaryMinus.vi	rotation2d unaryminus( )				
							rotation2d new()	can use cluster constant			

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
ROTATION3D	Χ	Χ		Χ	SI		Rotation3d_Create_AxisAngle.vi					
	Χ	Χ		Χ	SI		Rotation3d_Create_Default.vi					
	Χ	Χ		Χ	SI		Rotation3d_Create_Quaternion.vi					
	Χ	Χ		Χ	1		Rotation3d_Create_InitialFinalVector.vi					
	Χ	Χ		Χ	SI		Rotation3d_Create_RollPitchYaw.vi					
	Χ	Χ		X	I		Rotation3d_Create_RotMatrix.vi					
	Χ	Χ		X	SI		Rotation3d_Div.vi					
	Χ	Χ		Χ	SI		Rotation3d_Equals.vi					
	X	Χ	X	Χ	SI		Rotation3d_GetAxisAngle.vi					
	X	X		X	SI		Rotation3d_GetQuaternion.vi					
	X	X		X	SI		Rotation3d_GetXYZ.vi					
•	X	X		X	SI		Rotation3d_Interpolate.vi					
•	X	X		X	SI		Rotation3d_Minus.vi					
	X	X		X	SI		Rotation3d_Plus.vi					
	X	X		X	SI		Rotation3d_RotateBy.vi					
	X	X		X	SI SI		Rotation3d_Times.vi					
	X	X		$\frac{\lambda}{X}$	SI		Rotation3d_ToRotation2d.vi					
	^	^		^	SI		Rotation3d_UnaryMinus.vi				-	

	Implemented Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
TRANSFORM2D	XX	·	X	SI			Transform2d_Create_PosePose.vi	transform2d new( pose2d, pose2d )				

mation Lis	,,										
,											
	X	X		X	SI		Transform2d_Create_TransRot.vi	transform2d new( translation2d, rotation2d )			
	X	X		Χ	SI		Transform2d Div.vi				
	X	X		X	SI		Transform2d Equals.VI	boolean equals( other transform2d )			
-											
	X	X		X	SI		Transform2d_GetRotation.VI	rotation2d getRotation() use cluster unpack			
	X	X		Χ	SI		Transform2d_GetTranslation.VI	translation2d getTranslation() use cluster unpack			
	X	X	X	X	SI		Transform2d_GetXY.vi				
	X	X	Χ	X	SI		Transform2d_GetXYAngle.vi				
	Х	X		X	SI		Transform2d Inverse.vi	transform inverse() new			
								transform inverse()			
	X	X		X	Si		Transform2d_Plus.vi				
	X	X		Χ	SI		Transform2d_Times.vi	transform2d times( double scalar )			
								transform2d new( ) can use cluster constant			
SFORM3D	X X X Implemented	X X Documented	Not WPILIB	X Wenu Item	ର ଓ ଓ Execution Optimi	Test Routine	VI Name  Transform3d_Create_Default.vi  Transform3d_Create_Pose3dPose.3dv  Transform3d_Create_Trans3dRot3d.vi  Transform3d_Div.vi		Code Review	Test Program	Error Checking
ŀ			-								_
	X	Χ		Χ	SI		Transform3d_Equals.VI				-
	Χ	X		Χ	SI		Transform3d_GetRotation3d.VI				
	X	X		X	SI		Transform3d GetTranslation3d.VI				
	X		Χ	X	SI		Transform3d GetXYZ.vi				
	X	X		$\hat{X}$	SI		Transform3d Inverse.vi				
			+			+					
	X	X		X	Si		Transform3d_Plus.vi				
	Χ	X		Χ	SI		Transform3d_Times.vi				
	ented	ənted	יור וB	em.	on Optimized	utine	Program		eview	ogram	hecking
	nplemented	ocumented	lot WPILIB	lenu Item		est Routine	ample Program	Function Drototyne	ode Review	est Program	iror Checking
A TIONAD D	Implemented	Documented	Not WPILIB	Menu Item	Execution	Test Routine	ପୁର VI Name	Function Prototype Notes	Code Review	Test Program	Error Checking
ATION2D	X	Χ	Not WPILIB	Χ	S Execution	Test Routine	vi Name  Translation2d_Create_DistAng.vi		Code Review	Test Program	Error Checking
ATION2D	X	X X	Not WPILIB	X X	S Execution	Test Routine	VI Name  Translation2d_Create_DistAng.vi  Translation2d_Create.vi	Function Prototype Notes translation2d new( double x, double y )	Code Review	Test Program	Error Checking
ATION2D	X	X X X	Not WPILIB	X X X	IS Execution	Test Routine	VI Name Translation2d_Create_DistAng.vi Translation2d_Create.vi Translation2d_Div.vi	translation2d new( double x, double y )	Code Review	Test Program	Error Checking
ATION2D	X X X	X X X	Not WPILIB	X X X	IS Execution	Test Routine	VI Name Translation2d_Create_DistAng.vi Translation2d_Create.vi Translation2d_Div.vi	translation2d new( double x, double y )	Code Review	Test Program	Error Checking
ATION2D	X X X	X X X X	Not WPILIB	X X X X	IS IS Execution	Test Routine	VI Name Translation2d_Create_DistAng.vi Translation2d_Create.vi Translation2d_Div.vi Translation2d_Equals.vi		Code Review	Test Program	Emor Checking
ATION2D	X X X X	X X X X	Not WPILIB	X X X X	IS IS Execution	Test Routine	VI Name  Translation2d_Create_DistAng.vi Translation2d_Create.vi Translation2d_Div.vi Translation2d_Equals.vi Translation2d_Equals.vi Translation2d GetAngle.vi	translation2d new( double x, double y )  boolean equals( translation other )	Code Review	Test Program	Emor Checking
ATION2D	X X X X X	X X X X X	Not WPILIB	X X X X X	IS IS Execution	Test Routine	VI Name  Translation2d_Create_DistAng.vi Translation2d_Create.vi Translation2d_Div.vi Translation2d_Equals.vi Translation2d_GetAngle.vi Translation2d_GetDistance.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )	Code Review	Test Program	Error Checking
ATION2D	X X X X X X	X X X X X X	Not WPILIB	X X X X X X	IS IS Execution	Test Routine	VI Name Translation2d_Create_DistAng.vi Translation2d_Create.vi Translation2d_Div.vi Translation2d_Equals.vi Translation2d_GetAngle.vi Translation2d_GetDistance.vi Translation2d_GetNorm.VI	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  can use cluster unpack	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X	X X X X X X X	Not	X X X X X X	IS IS Execution	Test Routine	VI Name Translation2d Create DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetDistance.vi Translation2d GetNorm.VI Translation2d GetX.VI	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X X	X X X X X X X X	Not WPILIB	X X X X X X X X	IS I	Test Routine	VI Name Translation2d Create_DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetDistance.vi Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetXY.VI	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  can use cluster unpack double getX()  can use cluster unpack	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X	X X X X X X X	Not	X X X X X X	IS I	Test Routine	VI Name Translation2d Create DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetDistance.vi Translation2d GetNorm.VI Translation2d GetX.VI	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  can use cluster unpack	Code Review	Test Program	Emor Checking
ATION2D	X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X		Test Routine	VI Name Translation2d Create_DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetDistance.vi Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetXY.VI Translation2d GetY.VI Translation2d GetY.VI	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  can use cluster unpack double getX()  can use cluster unpack	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X		Test Routine	VI Name Translation2d Create_DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetDistance.vi Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetXY.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  can use cluster unpack  double getY()  can use cluster unpack	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X X X X X X X X X X		Test Routine	VI Name Translation2d Create_DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetXy.VI Translation2d GetXy.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  can use cluster unpack  double getY()  can use cluster unpack	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X X X X X X X X X X		Test Routine	VI Name Translation2d Create_DistAng.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetXY.VI Translation2d GetXY.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d plus( translation2d other )	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X X X X X X X X X X	10   10   10   10   10   10   10   10	Test Routine	VI Name Translation2d Create DistAng.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetX.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d Plus.vi Translation2d RotateBy.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )	Code Review	Test Program	Emor Checking
ATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X X X X X X X X X X	S	Test Routine	VI Name Translation2d Create DistAng.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetX.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d Plus.vi Translation2d RotateBy.vi Translation2d Times.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )	Code Review	Test Program	Emor Checking
ATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X X X X X X X X X X	10   10   10   10   10   10   10   10	Test Routine	VI Name Translation2d Create DistAng.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetX.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d Plus.vi Translation2d RotateBy.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus()	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X X X X X X X X X X	S	Test Routine	VI Name Translation2d Create DistAng.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetX.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d Plus.vi Translation2d RotateBy.vi Translation2d Times.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus( )  translation2d new()  can use cluster unpack	Code Review	Test Program	Error Checking
ATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X X X X X X X X X X	S	Test Routine	VI Name Translation2d Create DistAng.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetX.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d Plus.vi Translation2d RotateBy.vi Translation2d Times.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus( )  translation2d new()  can use cluster unpack	Code Review	Test Program	Error Checking
LATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	X X X X X X X X X X X X X X X X X X X	S	Test Routine	VI Name Translation2d Create DistAng.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetX.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d Plus.vi Translation2d RotateBy.vi Translation2d Times.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus()	Code Review	Test Program	Error Checking
.ATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not	Menu Item		Test Routine	VI Name  Translation2d Create_DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetDistance.vi Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetXY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d RotateBy.vi Translation2d Times.vi Translation2d UnaryMinus.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus( )  translation2d new()  can use cluster unpack	Code Review	Test Program	Error Checking
	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	WPILIB X Not	Menu Item	10   10   10   10   10   10   10   10		VI Name  Translation2d Create DistAng.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Interpolate.vi Translation2d Plus.vi Translation2d Plus.vi Translation2d RotateBy.vi Translation2d Times.vi Translation2d UnaryMinus.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus()  translation2d new()  can use cluster unpack  can use cluster unpack		Program	Checking
	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	WPILIB X Not	X Wenu Item X	10   10   10   10   10   10   10   10		VI Name  Translation2d Create_DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetXY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d RotateBy.vi Translation2d Times.vi Translation2d UnaryMinus.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus()  translation2d new()  can use cluster unpack  can use cluster unpack		Program	Checking
	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	WPILIB X Not	X X X X X X X X X X X X X X X X X X X	19   19   19   19   19   19   19   19		VI Name  Translation2d Create_DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Plus.vi Translation2d Plus.vi Translation2d Times.vi Translation2d UnaryMinus.vi Translation2d UnaryMinus.vi Translation2d Times.vi Translation2d UnaryMinus.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus()  translation2d new()  can use cluster unpack  can use cluster unpack		Program	Checking
LATION2D	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	WPILIB	X	10   10   10   10   10   10   10   10		VI Name  Translation2d Create_DistAng.vi Translation2d Create.vi Translation2d Div.vi Translation2d Equals.vi Translation2d GetAngle.vi Translation2d GetNorm.VI Translation2d GetNorm.VI Translation2d GetX.VI Translation2d GetXY.VI Translation2d GetY.VI Translation2d Interpolate.vi Translation2d Minus.vi Translation2d Plus.vi Translation2d RotateBy.vi Translation2d Times.vi Translation2d UnaryMinus.vi	translation2d new( double x, double y )  boolean equals( translation other )  double getDistance( translation2d other )  double getNorm()  double getX()  can use cluster unpack  double getY()  can use cluster unpack  translation2d minus( translation2d other )  translation2d plus( translation2d other )  translation2d rotateBy( rotation2d other )  translation2d times( double scalar )  translation2d unaryminus()  translation2d new()  can use cluster unpack  can use cluster unpack		Program	Checking

Revision 3.04 2/11/2023 – Added new pose est2												
		X		Χ	SI		Translation3d_GetDistance.vi					
	X	X	\ <u></u>	X	SI		Translation3d_GetNorm.VI					:
	X	X	X	X	SI		Translation3d_GetXYZ.vi Translation3d_Interpolate.vi					
	X			X	SI		Translation3d Minus.vi					
	X	X		X	SI		Translation3d Plus.vi					
	X				SI		Translation3d_RotateBy.vi					
	X	X		X	SI		Translation3d Times.vi					
	X			Χ	SI		Translation3d_ToTranslation2d.vi					
	X	X		Χ	SI		Translation3d_UnaryMinus.vi					
TWIST2	X X   X   X   X   X   X   X   X   X	X	Not WPILIB X Not WPILIB	X X Menu Item	Execution Optimized	X Test Routine  Sample Program  Sample Program	VI Name Twist2d_Create.vi Twist2d_Equals.VI Twist2d_GetAll.VI  VI Name Twist3d_Create.vi	Function Prototype  twist new( x, y, theta )  boolean equals( obj other )  Function Prototype	Notes	Code Review Code Review	Test Program	Error Checking
TWIST3					SI	X						
	X	X	X	X	SI	X	Twist3d_Equals.VI Twist3d_GetAll.VI					
		Ι Λ	Λ	<i>X</i>	31	Χ	TWISCO_GETAIL.VI					
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KINEMATICS												
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	olemented	cumented	t WPILIB	1enu Item	ecution Optimized	Test Routine Sample Program				de Review	st Program	or Checking
	Imp	Do	Not	~	Exe	Test	VI Name	Function Prototype	Notes	Š	7e.	Eur
CHASSIS SPEED				Χ	SI		ChassisSpeeds_FromFieldRelativeChassisSpeeds.VI					
	X	X		X	SI		ChassisSpeeds_FromFieldRelativeSpeeds.VI	chassisspeeds fromFieldRelativeSpeeds( double x, double y,				
	Y	X	Y	X	SI		ChassisSPeeds_GetXYOmega.vi	double angvel, rotation2d robotangle )	+			
	X	$\hat{x}$	^	$\hat{x}$	SI		ChassisSpeeds_New.vi	chassisspeeds new ( double xvel, double yvel, double angvel )				
							<u> </u>	chassisspeeds new ()	can use cluster constant			
	plemented	ocumented	ot WPILIB	enu Item	ecution Optimized	st Routine ample Program				ode Review	st Program	ror Checking
	lu l	_ <u>```</u>	≥ .	×	Ĭ,	Test	VI Name	Function Prototype	Notes	Cod		Ē
DIFFERENTIAL DRIVE KINEMATICS				X		X	DiffKinematics_New.vi	diffDriveKine new( double trackWidth )				:
	X	X		X	X	X	DiffKinematics_toChassisSpeed.vi	chassisSpeeds toChassisSpeeds( diffDrWheelSpeeds )				
	X	X		X	SI	Y	DiffKinematics_ToTwist2d.vi DiffKinematics_toWheelSpeed.vi	diffDriveWheelSpeed toWheelSpeeds( chassisSpeeds )				
	Λ	_ X		^	SI	^	Difficilientatics_townleetopeed.vi	difficultive write-induced control c				
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking

WPILib LabVIEW Math Library - VI Implementation List Revision 3.04 2/11/2023 – Added new pose est2 DIFFERENTIAL DRIVE ODOMETRY DiffOdometry\_Execute.vi DONT NEED Χ DiffOdometry\_Update.vi pose2d update( rotation2d gyro, double leftdist, double right dist ) Incorporates enhanced reset diffDrOdom new( rotation gyro, pose initial ) diffDrOdom new( rotation gyro ) void resetPosition( pose2d, rotation2d ) incorporated into "update" pose2d getPoseMeters() Function Prototype Notes DIFFERENTIAL DRIVE ODOMETRY 2 DiffDrvOdom2 Execute.vi X Replacement for orig diff drive XX DiffDrvOdom2 GetPose.vi X X X X DiffDrvOdom2\_New.vi X 1 X SI DiffDrvOdom2\_Reset.vi DiffDrvOdom2 Update.vi Χ Function Prototype Notes DIFFERENTIAL DRIVE WHEEL SPEEDS diffDrWheelSpeeds new() diffDrWheelSpeeds new( double leftVel, double rightVel ) XX DiffWheel Normalize.vi void normalize( double maxVel ) Function Prototype Notes MECANUM DRIVE KINEMATICS X X Χ MecaKinematics New.vi X X X X X X Χ MecaKinematics SetInverseKinematics.vi MecaKinematics\_ToChassisSpeeds.vi X MecaKinematics ToTwist2d.vi Χ Χ X X MecaKinematics ToWheelSpeeds.vi Χ MecaKinematics\_ToWheelSpeedsZeroCenter.vi Χ VI Name Function Prototype Notes MECANUM DRIVE MOTOR VOLTAGE

Function Prototype

Notes

VI Name

MecaOdometry\_Execute.vi MecaOdometry GetKinematics.vi

MecaOdometry\_GetPose.vi

MecaOdometry New.vi

Χ

X

XX

XX

MECANUM DRIVE ODOMETRY

X	( )	Υ	X									
		/		_			MecaOdometry_NewDefaultPose.vi					
			X				MecaOdometry_Reset.VI					
_	( )	Υ	X		_		MecaOdometry_Update.vi		Demoved			
							MecaOdometry_UpdateWithTime.vi		Removed			
	( )		$\overline{X}$	SI		Sample Program	MecaWheelPos_Get.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
	( )	<u>'</u>	X		+		MecaWheelPos_New.vi MecaWheelPos_Sub.vi					
	<u> </u>	`		- 0,			INICCAVVIICCII 03_0ub.vi					
MECANUM DRIVE WHEEL SPEEDS X	2		X Menu Item		Test Routine	Sample Program	VI Name MecaWheel_New.Vi	Function Prototype  public MecanumDriveWheelSpeeds(double frontLeftMetersPerSecond, double frontRightMetersPerSecond, double rearLeftMetersPerSecond, double	Notes	Code Review	Test Program	Error Checking
	, ,	v V	V	0/			Marshall Catallai	rearRightMetersPerSecond, double				
$\frac{x}{x}$	( )	X X	X				MecaWheel_GetAll.vi MecaWheel Normalize.vi	public void normalize(double				
^	`   ′	`	^	^			Iviecavvileer_Normalize.vi	attainableMaxSpeedMetersPerSecond)				
molemented		Vot WPILIB	Menu Item	Execution Opt	Test Routine	Sample Progra	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
SWERVE DRIVE KINEMATICS X		$\overline{X}$	X		T	Τ,	SwerveKinematics_New4.VI	71	For 4 module drives			
X	( )	( X	X				SwerveKinematics_NewX.VI		uses array as input			
X		X					SwerveKinematics_NormalizeWheelSpeeds.vi	public static void normalizeWheelSpeeds(SwerveModuleState[] moduleStates, double attainableMaxSpeedMetersPerSecond)				
X	( )	<i>X</i>	X				SwerveKinematics_ToChassisSpeeds4.VI	,	For 4 module drives			
		X X					SwerveKinematics_ToChassisSpeedsX.VI	LE O. M. L. O. L. F.	uses array as input			
X		×	X				SwerveKinematics_ToSwerveModuleStates.VI	public SwerveModuleState[] toSwerveModuleStates(ChassisSpeeds chassisSpeeds, Translation2d centerOfRotationMeters)				
	( )		X				SwerveKinematics_ToSwerveModuleStatesZeroCenter.VI	public SwerveModuleState[] toSwerveModuleStates(ChassisSpeeds chassisSpeeds)				
<u> </u>	( )	<b>Κ</b>	X				SwerveKinematics_ToTwist2d4.VI SwerveKinematics_ToTwist2dX.VI					
								public SwerveDriveKinematics(Translation2d wheelsMeters)	variable parameters (replace with array and "4" calls)			
								public ChassisSpeeds toChassisSpeeds(SwerveModuleState wheelStates)	variable parameters (replace with array and "4" calls)			
pape		Documented Not WPILIB	Menu Item	Execution Optimized	Test Routine	imple Program			anay unu + vanoj	Code Review	st Program	Error Checking
n	5 6	ડ ક	¥	Ě		San	VI Name	Function Prototype	Notes	ပိ	Test	En
Implemented							SwerveOdometry_Execute4.vi					
SWERVE DRIVE ODOMETRY						_						
SWERVE DRIVE ODOMETRY							SwerveOdometry_ExecuteX.vi	with Decod with a Material				
SWERVE DRIVE ODOMETRY	( )		X				SwerveOdometry_GetPosition.VI	public Pose2d getPoseMeters()				
SWERVE DRIVE ODOMETRY  X		Υ	X X					public Pose2d getPoseMeters() public SwerveDriveOdometry(SwerveDriveKinematics kinematics, Rotation2d gyroAngle, Pose2d initialPose) public SwerveDriveOdometry(SwerveDriveKinematics kinematics, Rotation2d gyroAngle)				

023 – Added new pose est2													
	X	Χ	Χ	X				SwerveOdometry_Update4.VI		For 4 module drives			
								SwerveOdometry_UpdateWithTime4.VI		REMOVED			
							(	SwerveOdometry_UpdateWithTimeX.VI		REMOVED			
	X	Χ	X	X			Ç	SwerveOdometry_UpdateX.VI		uses array as input			
									public Pose2d updateWithTime(double currentTimeSeconds,	variable parameters (replace with			
									Rotation2d gyroAngle, SwerveModuleState moduleStates)	array and "4" calls)			
									public Pose2d update(Rotation2d gyroAngle, SwerveModuleState moduleStates)	variable parameters (replace with array and "4" calls)			
	ted	pe <sub>q</sub>	B	,	Optimized	ine	rogram				iew	ram	cking
	nplemente	Documente	Vot WPILIB	ltem	Execution	Test Routine	ď				Şe.	ρο	he
	em	<u> </u>	¥	u li	nt	ĕ	Sample				E E	ď	Ő
	ďι	OC	ot	Menu	ě	est	au,	// NI=	Franchisco Dantoh ma	Natas	po	est	5
			Ž			<u> </u>		/I Name	Function Prototype	Notes	ပိ	ĭ	ш́.
VERVE DRIVE MODULE POSITIONS				Χ	SI			SwerveModulePosition_CompareTo.vi					
	X				SI			SwerveModulePosition_Equals.vi					
	X			X	SI			SwerveModulePosition_Get.vi					
	X	X		Χ	SI		(	SwerveModulePosition_New.vi					
	$\Box$												
	mplemented	Documented	Vot WPILIB	Menu Item	Execution Optimize	Test Routine	Sample Program				de Review	st Program	or Checking
	m,	ŏ	δ	Me	ŭ	<u>Te</u> s	Sa,	/I Name	Function Prototype	Notes	Cod	7e	Į.
SWERVE DRIVE MODULE STATE	$\overline{X}$	X	$\neg$		SI	·		SwerveModuleState CompareTo.vi	public int compareTo(SwerveModuleState o)			•	
	X			X	SI			SwerveModuleState Equal.vi					
	X		$\overline{}$	X				SwerveModuleState Get.vi					
	X		$\longrightarrow$		SI			SwerveModuleState_New.vi	public SwerveModuleState(double speedMetersPerSecond,				
	^	^	ļ	_ ^	<i>O</i> ,		ľ	ower vermodule etate_ive w.vi	Rotation2d angle)				
	X	X		X	SI			SwerveModuleState_Optimize.vi	public SwerveModuleState optimize( SwerveModuleState desired,				
									Rotation2d angle )				
	Implemented	Documented	Not WPILIB	Menu Item	ecution Optimized	st Routine	mple Program	/I Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
			<	2	Ехес	Test	Sa	/i Name			0		
CUBIC HERMITE SPLINE			_		Ě			·	protected SimpleMatrix getCoefficients()	not needed, use cluster unpack	<u> </u>		
CUBIC HERMITE SPLINE				X	Ë	7es		CubicHermiteSpline_getControlVectorFromArrays.vi	protected SimpleMatrix getCoefficients() private SimpleMatrix getControlVectorFromArrays( double[]				
CUBIC HERMITE SPLINE		X			Ë	7es	(	·	protected SimpleMatrix getCoefficients() private SimpleMatrix getControlVectorFromArrays( double[] initialVector, double[] finalVector) private SimpleMatrix makeHermiteBasis()				
CUBIC HERMITE SPLINE	X	X		X	Ĕ		(	CubicHermiteSpline_getControlVectorFromArrays.vi	protected SimpleMatrix getCoefficients() private SimpleMatrix getControlVectorFromArrays( double[] initialVector, double[] finalVector)				
CUBIC HERMITE SPLINE	Implemented X X X	X	Not WPILIB	X	9 Execution Optimized Ex	coutine	Sample Program	CubicHermiteSpline_getControlVectorFromArrays.vi	protected SimpleMatrix getCoefficients() private SimpleMatrix getControlVectorFromArrays( double[] initialVector, double[] finalVector) private SimpleMatrix makeHermiteBasis() public CubicHermiteSpline(double[] xInitialControlVector, double[] xFinalControlVector, double[] yInitialControlVector, double[] yFinalControlVector)  Function Prototype public PoseWithCurvature(Pose2d poseMeters, double		Code Review	Test Program	Error Checking
	Implemented X X X	X X X X	мыгів	Menu Item X	Execution Optimized	coutine	Sample Program	CubicHermiteSpline_getControlVectorFromArrays.vi CubicHermiteSpline_makeHermiteBasis.vi CubicHermiteSpline_New.vi	protected SimpleMatrix getCoefficients() private SimpleMatrix getControlVectorFromArrays( double[] initialVector, double[] finalVector) private SimpleMatrix makeHermiteBasis() public CubicHermiteSpline(double[] xInitialControlVector, double[] xFinalControlVector, double[] yInitialControlVector, double[] yFinalControlVector)  Function Prototype public PoseWithCurvature(Pose2d poseMeters, double curvatureRadPerMeter)	not needed, use cluster unpack  Notes	de Review	Test Program	Error Checking
	Implemented X X X	X X X X	мыгів	Menu Item X	Execution Optimized	coutine	Sample Program	CubicHermiteSpline_getControlVectorFromArrays.vi CubicHermiteSpline_makeHermiteBasis.vi CubicHermiteSpline_New.vi	protected SimpleMatrix getCoefficients() private SimpleMatrix getControlVectorFromArrays( double[] initialVector, double[] finalVector) private SimpleMatrix makeHermiteBasis() public CubicHermiteSpline(double[] xInitialControlVector, double[] xFinalControlVector, double[] yInitialControlVector, double[] yFinalControlVector)  Function Prototype public PoseWithCurvature(Pose2d poseMeters, double curvatureRadPerMeter) public PoseWithCurvature()	Notes  Can use cluster constant	de Review	Test Program	Error Checking
	Implemented X X X	X X X X	мыгів	Menu Item X	Execution Optimized	coutine	Sample Program	CubicHermiteSpline_getControlVectorFromArrays.vi CubicHermiteSpline_makeHermiteBasis.vi CubicHermiteSpline_New.vi	protected SimpleMatrix getCoefficients() private SimpleMatrix getControlVectorFromArrays( double[] initialVector, double[] finalVector) private SimpleMatrix makeHermiteBasis() public CubicHermiteSpline(double[] xInitialControlVector, double[] xFinalControlVector, double[] yInitialControlVector, double[] yFinalControlVector)  Function Prototype public PoseWithCurvature(Pose2d poseMeters, double curvatureRadPerMeter) public PoseWithCurvature() public Pose2d poseMeters	not needed, use cluster unpack  Notes	de Review	Test Program	Error Checking

'======= SPLINE '========

Added new pose est2					~								
					izec		_						
QUINTIC HERMITE SPLINE	× Implemented	X Documented	Not WPILIB	X Menu Item	Execu		Sample Program	VI Name  QuinticHermiteSpline_getControlVectorFromArrays.vi	Function Prototype private SimpleMatrix getControlVectorFromArrays(double[]	Notes	Code Review	Test Program	Error Checking
QUINTIC HERMITE SPLINE	<i>x</i>	^		^				QuintichermiteSpline_getControlvectorFromArrays.vi	initialVector, double[] finalVector)				
	X	X		X				QuinticHermiteSpline_makeHermiteBasis.vi	private SimpleMatrix makeHermiteBasis()				
	X	X		X				QuinticHermiteSpline_New.vi	public QuinticHermiteSpline(double[] xInitialControlVector, double[] xFinalControlVector, double[] yInitialControlVector, double[] yFinalControlVector) protected SimpleMatrix getCoefficients()	not needed, use cluster unpack			
									protected offipiewath's getocemeterist)	not needed, use cluster unpack			
SPLINE (Abstract class)	X Implemented	X Documented	Not WPILIB	X Menu Item	Exect	Total Control	Sample Program	VI Name Spline_getPoint.vi	Function Prototype public PoseWithCurvature getPoint(double t) Spline(int degree)	Notes	Code Review	Test Program	Error Checking
									Spline(int degree) public static class ControlVector				
									•	implemented as data structure			
	Implemented	Documented	WPILIB	ıu Item	Execution Optimized	- Giting 0	rest Koutine Sample Program				e Review	t Program	ır Checking
	du	000	Not	Menu	Exe	, ,	Sami	VI Name	Function Prototype	Notes	80	Test	Erro
SPLINE HELPER		X		X	SI		K	SplineHelp_GetCubicCtrlVector.vi	private static Spline.ControlVector getCubicControlVector(double scalar, Pose2d point) public static Spline.ControlVector[]			·	
	X						`	SplineHelp_GetCubicCtrlVectorsFromWayPts.vi	getCubicControlVectorsFromWaypoints( Pose2d start, Translation2d[] interiorWaypoints, Pose2d end )				
		X	X	X		_		SplineHelp_GetCubicCtrlVectorsFromWeightedWayPts.vi		:			
	X		X					SplineHelp_GetCubicSpline_Calc1.vi SplineHelp_GetCubicSpline_Calc2.vi		internal			
	X	X	$\frac{1}{X}$	No	,			SplineHelp GetCubicSpline Calc3.vi		internal			
	X	X		X		)	Υ	SplineHelp_getCubicSplinesFromControlVectors.vi	public static CubicHermiteSpline[] getCubicSplinesFromControlVectors( Spline.ControlVector start, Translation2dfl waypoints, Spline ControlVector end)				
	X	X		X	SI	'		SplineHelp_GetQuinticCtrlVector.vi	Translation2d[] waypoints, Spline.ControlVector end) private static Spline.ControlVector getQuinticControlVector(double				
								SplineHelp_GetQuinticCtrlVectorsFromWayPts.vi	scalar, Pose2d point) public static List <spline.controlvector> getQuinticControlVectorsFromWaypoints( List<pose2d> waypoints )</pose2d></spline.controlvector>	REMOVED 2762			
	X	X		X				SplineHelp_GetQuinticCtrlVectorsFromWeightedWayPts.vi SplineHelp_getQuinticSplinesFromControlVectors.vi	public static QuinticHermiteSpline[] getQuinticSplinesFromControlVectors( Spline.ControlVector[] controlVectors)	REMOVED 2762			
			X					SplineHelp_GetQuinticSplinesFromWeightedWayPts.vi		New 2762			
	X	X		No				SplineHelp_GetQuinticSplinesFromWayPts.vi SplineHelp_ThomasAlgorithm.vi	private static void thomasAlgorithm(double[] a, double[] b, double[] c, double[] d, double[] solutionVector)	New 2762 internal			
SPLINE PARAMETERIZER	X Implemented	X Documented	Not WPILIB	X Menu Item	Execu	Tooler Control	Sample Program	VI Name SplineParam_Spline_T0_T1.vi	Function Prototype  public static List <posewithcurvature> parameterize(Spline spline,</posewithcurvature>	Notes	Code Review	Test Program	Error Checking
	X	X	-	X		-	X	SplineParam_Spline.vi	double t0, double t1)  public static List <posewithcurvature> parameterize(Spline spline)</posewithcurvature>				
	Χ	X	X	No	)			SplineParam_StackGet.vi		internal			

Revision 3.04 2/11/2023 – Added new pose est2

<i>x</i>	X   )	( No	SplineParam_StackPop.vi	internal		
X	x >	( No	SplineParam StackPush.vi	internal		

public double getStartVelocity()

can use cluster unpack

'======= **TRAJECTORY** '======= VI Name Function Prototype Notes **TRAJECTORY** Χ Trajectory Concatenate.vi Trajectory equals.vi boolean equals( other obj ) **FUTURE** Χ Χ Χ SI Trajectory GetStates.vi public List<State> getStates() not needed, use unpack XX X SI Trajectory GetTotalTime.vi public double getTotalTimeSeconds() not needed, use unpack Χ Χ No SI Trajectory lerp double.vi private static double lerp(double startValue, double endValue, double t) X Χ No SI private static Pose2d lerp(Pose2d startValue, Pose2d endValue, Trajectory\_lerp\_Pose.vi double t) X Χ Χ SI Trajectory\_New\_Empty.vi XX X SI Trajectory\_New.vi public Trajectory(final List<State> states) XX Trajectory RelativeTo.vi public Trajectory relativeTo(Pose2d pose) X Trajectory\_Sample.vi public State sample(double timeSeconds)  $X \mid X$ X Sample in reverse order. Negate X Trajectory\_SampleReverse.vi  $X \mid X$ Χ public Trajectory transformBy(Transform2d transform) XX Χ Trajectory TransformBy.vi public Pose2d getInitialPose() can use cluster unpack, array index Function Prototype Notes TRAJECTORY STATE X X SI TrajectoryState\_Equals.vi boolean equals( other obj ) Χ XX Χ SI TrajectoryState GetAll.vi XX X SI TrajectoryState GetPose.vi State interpolate(State endValue, double i) TrajectoryState\_Interpolate.vi  $X \mid X$ X public State(double timeSeconds, double TrajectoryState\_New.vi SI velocityMetersPerSecond, double accelerationMetersPerSecondSq, Pose2d poseMeters, double curvatureRadPerMeter) public State() Function Prototype TRAJECTORY CONFIG X TrajectoryConfig AddConstraint.vi public TrajectoryConfig addConstraint(TrajectoryConstraint Implemented differently, can't constraint) duplicate. public TrajectoryConfig addConstraints(List<? extends Implemented differently, can't Χ TrajectoryConfig\_AddConstraints.vi X TrajectoryConstraint> constraints) Χ X Χ SI TrajectoryConfig Create.vi public TrajectoryConfig(double maxVelocityMetersPerSecond, double maxAccelerationMetersPerSecondSq) X TrajectoryConfig GetCentripetalAccel.vi X X X X TrajectoryConfig\_GetConstraints.vi public List<TrajectoryConstraint> getConstraints() Implemented differently, can't Χ duplicate. TrajectoryConfig\_GetEndVelocity.vi XX Χ can use cluster unpack public double getEndVelocity() Χ TrajectoryConfig GetKinematicsDiffDrive.vi Χ Χ

TrajectoryConfig GetKinematicsMecanumfDrive.vi

TrajectoryConfig GetKinematicsSwerveDrive.vi

TrajectoryConfig GetMaxVelAccel.vi

TrajectoryConfig\_GetStartVelocity.vi

TrajectoryConfig GetVoltageDiffDrive.vi

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 $X \mid X \mid$ 

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X	X		X			TrajectoryConfig IsReversed.vi	public boolean isReversed()	can use cluster unpack	
Χ	Χ	Х	Χ	SI		TrajectoryConfig setCentripetalAccel.vi	, v	·	
Χ	X		X			TrajectoryConfig_SetEndVelocity.vi	public TrajectoryConfig setEndVelocity(double endVelocityMetersPerSecond)		
X	Х		X	SI		TrajectoryConfig_setKinematicsDiffDrive.vi	public TrajectoryConfig setKinematics(DifferentialDriveKinematics kinematics)		
Χ	Х		Х	SI		TrajectoryConfig_setKinematicsMecanumfDrive.vi	public TrajectoryConfig setKinematics(MecanumDriveKinematics kinematics)		
X	X		X	SI		TrajectoryConfig_setKinematicsSwerveDrive.vi	public TrajectoryConfig setKinematics(SwerveDriveKinematics kinematics)		
Χ	Χ		X	SI		TrajectoryConfig setReversed.vi	public TrajectoryConfig setReversed(boolean reversed)		
X	Х		X			TrajectoryConfig_SetStartVelocity.vi	public TrajectoryConfig setStartVelocity(double startVelocityMetersPerSecond)		
X	Χ	X	Χ	SI		TrajectoryConfig_setVoltageDiffDrive.vi	, i		
							public double getMaxVelocity()	Created function to return both	
							public double getMaxAcceleration()	Created function to return both	
		•			•		NOTE ADD OTHER "SET" ROUTINES FOR OTHER CONTRAINTS HERE, SINCE NEW CONTRAINTS ARE SPECIFIC AND NOT GENERIC.		

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
TRAJECTORY GENERATE	X	X		X				TrajectoryGenerate_Make_Cubic_CtrlVect.vi	public static Trajectory generateTrajectory( Spline.ControlVector initial, List <translation2d> interiorWaypoints, Spline.ControlVecto end, TrajectoryConfig config)</translation2d>	uses cubic splines			
	X	X		X				TrajectoryGenerate_Make_Cubic.vi	public static Trajectory generateTrajectory( Pose2d start, List <translation2d> interiorWaypoints, Pose2d end, TrajectoryConfig config)</translation2d>	uses cubic splines			
	Χ	Χ	Χ	Χ				TrajectoryGenerate_Make_Generic.vi	Helper to bring these all together	Use this one!!!			
	X	Х		X				TrajectoryGenerate_Make_Quintic_CtrlVect.vi	public static Trajectory generateTrajectory( ControlVectorList controlVectors, TrajectoryConfig config)	uses quintic splines			
	Χ	Χ	X	X				TrajectoryGenerate_Make_Quintic_Weighted.vi	, , , , , , , , , , , , , , , , , , , ,	New 2762			
	X	X		X				TrajectoryGenerate_Make_Quintic.vi	public static Trajectory generateTrajectory(List <pose2d> waypoints, TrajectoryConfig config)</pose2d>	uses quintic splines			
	X	X		X				TrajectoryGenerate_splinePointsFromSplines.vi	public static List <posewithcurvature> splinePointsFromSplines(Spline[] splines)</posewithcurvature>				
					pəz								

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimiz	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
TRAJECTORY GENERATE (Control Vector)									public ControlVectorList(int initialCapacity)	may not need, just data			
									public ControlVectorList()	may not need, just data			
									public ControlVectorList(Collection extends<br Spline.ControlVector> collection)	may not need, just data			

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
TRAJECTORY PARAMETERIZE	X	X	X	No				TrajectoryParam_calcStuffFwd.vi					
	X	Χ	Χ	No				TrajectoryParam_calcStuffRev.vi					
	X	Х		No				TrajectoryParam_enforceAccel.vi	private static void enforceAccelerationLimits(boolean reverse, List <trajectoryconstraint> constraints, ConstrainedState state)</trajectoryconstraint>	This routines needs to be changed when new constraints are added.			
	X	X	X	No				TrajectoryParam_enforceVelocity.vi		This routines needs to be changed when new constraints are added.			

WPILib LabVIEW Math Library - VI Implementation List Revision 3.04 2/11/2023 – Added new pose est2 public static Trajectory timeParameterizeTrajectory( List<PoseWithCurvature> points. List<TrajectoryConstraint> constraints, double TrajectoryParam timeParam.vi startVelocityMetersPerSecond, double endVelocityMetersPerSecond, double maxVelocityMetersPerSecond, double
maxAccelerationMetersPerSecondSq, boolean reversed) Function Prototype ConstrainedState(PoseWithCurvature pose, double TRAJECTORY PARAMETERIZE CONSTRAINED STATE X ConstrainedState New.vi distanceMeters, double maxVelocityMetersPerSecond, double minAccelerationMetersPerSecondSq, double maxAccelerationMetersPerSecondSq) ConstrainedState\_SetMaxAccel.vi X X X X ConstrainedState SetMinAccel.vi ConstrainedState SetVelAccel.vi ConstrainedState SetVelocity.vi X X X X ConstrainedState() Function Prototype Notes TrajectoryUtil\_fromPathWeaverJSON.vi TRAJECTORY UTIL X public static Trajectory fromPathweaverJson(Path path) Χ Χ TrajectoryUtil MakeWeightedWayPoint ENG.vi X X X X TrajectoryUtil\_MakeWeightedWayPoint.vi XX X Χ X TrajectoryUtil\_toPathWeaverJSON.vi public static void toPathweaverJson(Trajectory trajectory, Path public static Trajectory deserializeTrajectory(String json) public static String serializeTrajectory(Trajectory trajectory) Routine VI Name Function Prototype Notes TRAPEZOID PROFILE X TrapProfConstraint New.vi X X X Χ Χ TrapProfile Calculate.vi Χ TrapProfile Direct.vi No Private, remove from menu X X X X TrapProfile Execute.vi TrapProfile Execute AtGoal.vi X X X X SI XX TrapProfile\_IsFinished.vi Χ XX X TrapProfile New DefInitial.vi X X X X TrapProfile New.vi X TrapProfile\_ShouldFlipAcceleration.vi No Private, remove from menu XX Χ TrapProfile TimeLeftUntil.vi XX Χ TrapProfile\_TotalTime.vi TrapProfState Equals.vi XX X Χ TrapProfState New.vi '======== TRAJECTORY CONSTRAINT '======== Sample Program ecution Op rest Routine Not WPILIB

Function Prototype

Notes

TRIPETAL ACCELERATION CONSTRAINT	-		-	1/			10		
	X	X		X			CentripetalAccelConstraint_getMaxVelocity.vi	public double getMaxVelocityMetersPerSecond(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond)	
	X	X		X			CentripetalAccelConstraint_getMinMaxAccel.vi	public MinMax getMinMaxAccelerationMetersPerSecondSq(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond)	
	X	X		X	SI		CentripetalAccelConstraint_New.vi	public CentripetalAccelerationConstraint(double maxCentripetalAccelerationMetersPerSecondSq)	Can use cluster pack for now
					pe	•		<del>\</del>	
	nplemented	Documented	Vot WPILIB	Menu Item	Execution Optimized	Sample Program			
DIFF DRIVE KINEMATIC CONSTRAINT		X	_ <u>~</u>	<u> </u>	<u> </u>	Sa '	VI Name DiffDriveKinematicsConstraint_getMaxVelocity.vi	Function Prototype public double getMaxVelocityMetersPerSecond(Pose2d	Notes
DIT DRIVE RINEWATIC CONSTRAINT								poseMeters, double curvatureRadPerMeter, double velocitvMetersPerSecond)	
	X	X		X			DiffDriveKinematicsConstraint_getMinMaxAccel.vi	public MinMax getMinMaxAccelerationMetersPerSecondSq(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond)	
	X	X		X	SI		DiffDriveKinematicsConstraint_New.vi	public DifferentialDriveKinematicsConstraint(final DifferentialDriveKinematics kinematics, double maxSpeedMetersPerSecond)	
	plemente	Documented	Vot WPILIB	Menu Item	Execution Optimized	st Nouthre mple Program			
			8		Й,	Sam	VI Name	Function Prototype	Notes
DIFF DRIVE VOLTAGE CONSTRAINT		X		X			DiffDriveVoltageConstraint_getMaxVelocity.vi	public double getMaxVelocityMetersPerSecond(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond)	
	X	X		X			DiffDriveVoltageConstraint_getMinMaxAccel.vi	public MinMax getMinMaxAccelerationMetersPerSecondSq(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond)	
	X	X		X	SI		DiffDriveVoltageConstraint_New.vi	public DifferentialDriveVoltageConstraint(SimpleMotorFeedforward	
	1	t i						feedforward, DifferentialDriveKinematics kinematics, double	
					<i>p</i> <sub>6</sub>			feedforward, DifferentialDriveKinematics kinematics, double maxVoltage)	
	mented	mented	PILIB	Item	Optimized	Journal He Program		feedforward, DifferentialDriveKinematics kinematics, double	
	nplemented	ocumented	ot WPILIB	lenu Item	ution Optimized	ample Program	Millione	feedforward, DifferentialDriveKinematics kinematics, double maxVoltage)	Nucce
ELLIPTICAL REGION CONSTRAINT	mplemented	X Documented	Not WPILIB	Menu	ution Optimized	Sample Program	VI Name  EllipRegionConstraint_getMaxVelocity.vi	feedforward, DifferentialDriveKinematics kinematics, double	Notes
ELLIPTICAL REGION CONSTRAINT	X	X		X Wenu	ution Optimized	Sample Program	EllipRegionConstraint_getMaxVelocity.vi EllipRegionConstraint_getMinMaxAccel.vi	feedforward, DifferentialDriveKinematics kinematics, double maxVoltage)	Notes
ELLIPTICAL REGION CONSTRAINT	X X X	X X X		X X X	ution Optimized	Sample Program	EllipRegionConstraint_getMaxVelocity.vi EllipRegionConstraint_getMinMaxAccel.vi EllipRegionConstraint_IsPoseInRegion.vi	feedforward, DifferentialDriveKinematics kinematics, double maxVoltage)	Notes
ELLIPTICAL REGION CONSTRAINT	X X X	X		X Wenu	ution Optimized	Sample Program	EllipRegionConstraint_getMaxVelocity.vi EllipRegionConstraint_getMinMaxAccel.vi	feedforward, DifferentialDriveKinematics kinematics, double maxVoltage)	Notes
ELLIPTICAL REGION CONSTRAINT	x X X X	X X X	WPILIB	X X X	ecution Optimized Execution Optimized	ample Program Sam	EllipRegionConstraint_getMaxVelocity.vi EllipRegionConstraint_getMinMaxAccel.vi EllipRegionConstraint_IsPoseInRegion.vi EllipRegionConstraint_New.vi	feedforward, DifferentialDriveKinematics kinematics, double maxVoltage)  Function Prototype	
	X	X X X X Documented	Not WPILIB	Item X X X X	ution Optimized Execution Optimized	ram	EllipRegionConstraint_getMaxVelocity.vi EllipRegionConstraint_getMinMaxAccel.vi EllipRegionConstraint_IsPoseInRegion.vi EllipRegionConstraint_New.vi	feedforward, DifferentialDriveKinematics kinematics, double maxVoltage)  Function Prototype  Function Prototype	Notes
ELLIPTICAL REGION CONSTRAINT	X	X X X X Documented	WPILIB	Item X X X X	ecution Optimized Execution Optimized	ample Program Sam	EllipRegionConstraint_getMaxVelocity.vi EllipRegionConstraint_getMinMaxAccel.vi EllipRegionConstraint_IsPoseInRegion.vi EllipRegionConstraint_New.vi	feedforward, DifferentialDriveKinematics kinematics, double maxVoltage)  Function Prototype  Function Prototype	

Page 20 / 40 FRC\_LabVIEW\_Trajectory\_Library\_Routines.xlsx

					nize	,			
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optim	resi Rouillie Sampla Brogran			
	Imple	Оос	Not 1	Men	EX GC	יבא <i>ו</i>	VI Name	Function Prototype	Notes
MAX VELOCITY CONSTRAINT	Χ	Χ		X	SI		MaxVelocityConstraint_getMaxVelocity.vi	71	
	X	X			SI SI		MaxVelocityConstraint_getMinMaxAccel.vi MaxVelocityConstraint_New.vi		
					pə				
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimiz	rest Routifie Sample Drogram			
	эJdш	Joc	Vot 1	∕len	ixec	is a	VI Name	Function Prototype	Notes
MECANUM DRIVE KINEMATICS CONSTRAINT	Χ	Χ		X			MecaDriveKinematicsConstraint getMaxVelocity.vi		
	X	X		X	SI	+	MecaDriveKinematicsConstraint_getMinMaxAccel.vi MecaDriveKinematicsConstraint_New.vi		
	Implemented	Documented	WPILIB	Item	tion Optimized	rest Kodine Sampla Program			
	plen	cun	ot W	Menn	Execution	rest Rot			
RECTANGULAR REGION CONSTRAINT	<u>E</u>	X	Not	X	Щ I	2 2	VI Name RectRegionConstraint_getRectRegion.vi	Function Prototype	Notes
RESTANGUEAR REGION CONCINAINT	Χ	Χ		X			RectRegionConstraint getMinMaxAccel.vi		
	X	X		X X			RectRegionConstraint_lsPoseInRegion.vi RectRegionConstraint_New.vi		
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Semple Program	VI Name	Function Prototype	Notes
SWERVE DRIVE KINEMATICS CONSTRAINT	X	X		X			SwerveDriveKinematicsConstraint_getMaxVelocity.vi	public double getMaxVelocityMetersPerSecond(Pose2d poseMeters, double curvatureRadPerMeter, double	
	X	Х		X			SwerveDriveKinematicsConstraint_getMinMaxAccel.vi	velocityMetersPerSecond) public MinMax getMinMaxAccelerationMetersPerSecondSq(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond)	
	Х	Х		X	SI		SwerveDriveKinematicsConstraint_New.vi	Newpublic SwerveDriveKinematicsConstraint(final SwerveDriveKinematics kinematics, double maxSpeedMetersPerSecond)	Can use cluster pack for now
	Implemented	Documented	t WPILIB	Menu Item	Execution Optimized	rest Routine Semple Program			
TRAJECTORY CONSTRAINT	<u>E</u>		X	X	<del>й і</del>	2 C	VI Name TrajConstraint_GetMaxVelocity.vi	Function Prototype	Notes
TRAJECTORT CONSTRAINT	Χ	Χ	X	X			TrajConstraint_GetMinMaxAccel.vi		
The state of the s			Χ				TrajConstraint_GetType.vi		

Revision 3.04 2/11/2023 – Added new pose est2

'===== UTILITY '======

THESE ROUTINES ARE SPECIFIC TO LABVIEW. THEY DO NOT HAVE A

JAVA / C++ WPILIB EQUIVALENT

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Nample Program	Function Prototype Notes
UTIL		Χ	Χ	Χ	SI		Util_ApproxEqual.vi	
	Χ	Χ	Χ	Χ			Util_Array_PoseWCurv_to_XY.vi	
	Χ	Χ	Χ	Χ	SI		Util_CalcDist.vi	
	Χ	Χ	Χ	Χ	SI		Util_GetLibraryVersion.vi	
	Χ	Χ	Χ	Χ	SI		Util_GetLibUsage.vi	
	X	X	X	X			Util_GetTime.vi	Once tested completely, this should be optimized!
	Χ	Χ	Χ	No	1		Util_GetTime_U32.vi	
	Χ	Χ	Χ	No	I		Util_GetTime_U64.vi	
	Χ	Χ	Χ	No	N/A		Util_LibraryGlobals.vi	Global Variables – no block diag.
	Χ	Χ	Χ	Χ			Util_Trajectory_Absolute_To_Relative.vi	
	Χ	Χ	Χ	Χ			Util_Trajectory_ReadFile.vi	
	Χ	Χ	Χ	Χ			Util_Trajectory_to_XY.vi	
	Χ	Χ	Χ	No			Util_Trajectory_WriteFile_Config.vi	internal
	Χ	Χ	Χ	No			Util_Trajectory_WriteFile_OneState.vi	internal
	Χ	Χ	Χ	Χ			Util_Trajectory_WriteFile_PathFinder.vi	
	Χ	Χ	Χ	No			Util_Trajectory_WriteFile_PathFinderConfig.vi	internal
	Χ	Χ	Χ	Χ			Util_Trajectory_WriteFile_Pathweaver.vi	
	Χ	Χ	Χ	No			Util_Trajectory_WriteFile_States.vi	internal
	Χ	Χ	Χ	No			Util_Trajectory_WriteFile_WayPoints.vi	internal
	Χ	Χ	Χ	Χ			Util_Trajectory_WriteFile.vi	
	Χ	Χ	Χ	Χ			Util_TrajectoryState_Meters_To_Inches.vi	
	Χ	Χ	Χ	Χ			Util_TrajState_to_DiffDrive_WheelPos.vi	
	Χ	Χ	Χ	X			Util_DispWaypoint_Eng_To_Sl.vi	
	Χ	Χ	Χ	Χ			Util_DispWaypoint_To_CubicInput.vi	
	X	Χ	Χ	Χ			Util_DispWaypoint_To_QuinticInput.vi	
	Χ	Χ	Χ	Χ			Util_DispWeightedWaypiont_Eng_To_WeightedWaypoint	
	Χ	Χ	Χ	No			Util_DispWeightedWayPoint_To_WeightedWayPoint.vi	Sorry about the confusing name

'========

CONVERSIONS

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THESE ROUTINES ARE SPECIFIC TO LABVIEW. THEY DO NOT HAVE A

JAVA / C++ WPILIB EQUIVALENT

	mplemented	Oocumented	Vot WPILIB	Menu Item	Execution Optimized	Fest Routine	Sample Program	VI Name	Function Prototype	Notes
CONV	$\overline{x}$	$\overline{X}$	X	X	SI			Conv_AngleDegrees_Heading.vi		
	Χ	Χ	Χ	Χ	SI			Conv_AngleRadians_Heading.vi		
	Χ	X	Χ	Χ	SI			Conv_Centimeters_Meters.vi		
	Χ	X	Χ	Χ	SI			Conv_Deg_Radians.vi		
	Χ	Χ	Χ	Χ	SI			Conv_Deg_Rotations.vi		
	Χ	X	Χ	Χ	SI			Conv_Feet_Meters.vi		

X	Χ	X	Χ	SI	Conv_GyroDegrees_Heading.vi
X	Χ	Χ	Χ	SI	Conv_Heading_AngleRadians.vi
X	Χ	X	Χ	SI	Conv_Inches_Meters.vi
X	Χ	X	Χ	SI	Conv_Kilograms_Pounds.vi
X	Χ	Χ	Χ	SI	Conv_Meters_Feet.vi
X	Χ	X	Χ	SI	Conv_Meters_Inches.vi
X	Χ	X	Χ	SI	Conv_Pose2d_SI_Eng.vi
X	Χ	X	Χ	SI	Conv_Pounds_Kilograms.vi
X	Χ	X	Χ	SI	Conv_Radians_Deg.vi
X	Χ	Χ	Χ	SI	Conv_Radians_Rotations.vi
X	Χ	X	Χ	SI	Conv_Rotations_Deg.vi
X	Χ	X	Χ	SI	Conv_Rotations_Radians.vi
X	Χ	X	Χ	SI	Conv_Yards_Meters.vi

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimize	Test Routine	Sample Program	VI Name	Function Prototype	Notes
UNITS	Χ	Χ		X	SI			Units DegreesToRadians.vi		
	Χ	Х		X	SI			Units DegreesToRotations.vi		
	Χ	Χ		X	SI			Units_FeetToMeters.vi		
	Χ	Χ		X	SI			Units_InchesToMeters.vi		
	Χ	Χ		Χ	SI			Units_MetersToFeet.vi		
	Χ	Χ		Χ	SI			Units_MetersToInches.vi		
	Χ	Χ		X	SI			Units_MillisecondsToSeconds.vi		
	Χ	Χ		X	SI			Units_RadiansPerSecondToRotationsPerMinute.vi		
	Χ	Χ		Χ	SI			Units_RadiansToDegrees.vi		
	Χ	Χ		Χ	SI			Units_RadiansToRotations.vi		
	Χ	X		Χ	SI			Units_RotationsPerMinuteToRadiansPerSecond.vi		
	Χ	Χ		X	SI			Units_RotationsToDegrees.vi		
	Χ	X		X	SI			Units_RotationsToRadians.vi		
	X	X		X	SI			Units SecondsToMilliseconds.vi		

'====== PATHFINDER UTIL

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THESE ROUTINES ARE SPECIFIC TO LABVIEW. THEY DO NOT HAVE A JAVA / C++ WPILIB EQUIVALENT

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimizea	Test Routine	Sample Program	VI Name	Function Prototype
<b>PATHFINDERUTIL</b>	Χ	X	X	Χ				PathfinderUtil_Continuous_Heading_Difference.vi	
	Χ	X	X	Χ				PathfinderUtil_OptimizeTrajectoryStates.vi	
	Χ	Χ	X	Χ				PathfinderUtil_ToTrajectory.vi	
	X	X	X	X				PathfinderUtil_ToTrajectoryStates.vi	

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STATE SPACE MODEL '========

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
DC MOTOR	X	X		X	SI			DCMotor_GetAndymark9015.vi					
	X	X		Χ	SI			DCMotor_GetAndymarkAM2235A.vi					
	X	X		X	SI			DCMotor_GetAndymarkAM3493.vi					
	X	X		X	SI			DCMotor_GetAndymarkRs775_125.vi					
	Χ	X		Χ	SI			DCMotor_GetBag.vi					

Notes

X	Χ	X SI	DCMotor_GetBanebotsRs550.vi
X	Χ	X SI	DCMotor_GetBanebotsRs775.vi
X	Χ	X SI	DCMotor_GetCIM.vi
X	Χ	X SI	DCMotor_GetCurrent.vi
X	Χ	X SI	DCMotor_GetFalcon500.vi
X	Χ	X SI	DCMotor_GetMiniCIM.vi
X	Χ	X SI	DCMotor_GetNEO.vi
X	Χ	X SI	DCMotor_GetNEO550.vi
X	Χ	X SI	DCMotor_GetRomiBuiltIn.vi
X	Χ	X SI	DCMotor_GetSpeed.vi
X	Χ	X SI	DCMotor_GetTorque.vi
X	Χ	X SI	DCMotor_GetVex775Pro.vi
X	Χ	X SI	DCMotor_New.vi
X	Χ	X SI	DCMotor_PickMotor.vi
X	Χ	X SI	DCMotor_WithReduction.vi

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
LINEAR SYSTEM ID	X	X		X				LinearSystemId_CreateDCMotorSystem.vi					
	X	X		X				LinearSystemId_CreateDriveTrainVelocitySystem.vi		Update to use create matrix			
	Χ	X		X				LinearSystemId_CreateElevatorSystem.vi		Update to use create matrix			
	Χ	X		Χ				LinearSystemId_CreateFlywheelSystem.vi		Update to use create matrix			
	Χ	X		Χ				LinearSystemId_CreateSingleJointedArmSystem.vi		Update to use create matrix			
	X	X		X				LinearSystemId_IdentifyDriveTrainSystem.vi		Update to use create matrix			
	X	X		X				LinearSystemId_IdentifyPositionSystem.vi		Update to use create matrix			
	X	X		X				LinearSystemId_IdentifyVelocitySystem.vi		Update to use create matrix			

'======= STATE SPACE ESTIMATION '========

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimizec	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
DIFFERENTIAL DRIVE POSE ESTIMATOR	Χ	X		X				DiffDrivePoseEst_AddVisionMeasurement.vi					
	Χ	Χ		X				DiffDrivePoseEst_FillStateVector.vi					
	Χ	Χ		X				DiffDrivePoseEst_GetEstimatedPosition.vi					
	Χ	Χ		X				DiffDrivePoseEst_Kalman_F_Callback.vi					
	Χ	Χ		X				DiffDrivePoseEst_Kalman_H_Callback.vi					
	Χ	Χ		X				DiffDrivePoseEst_New.vi					
	Χ	X		X				DiffDrivePoseEst_ResetPosition.vi					
	Χ	X		X				DiffDrivePoseEst_SetVisionMeasurementStdDevs.vi					
	Χ	X		X				DiffDrivePoseEst_Update.vi					
	Χ	X		X				DiffDrivePoseEst_UpdateWithTime.vi					
	Χ	X		X				DiffDrivePoseEst_VisionCorrect_Callback.vi					
	Χ	X		X				DiffDrivePoseEst_VisionCorrect_Kalman_H_Callback.vi					

DIFFERENTIAL DRIVE POSE ESTIMATOR

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Χ	Χ		X				DiffDrivePoseEst2_AddVisionMeasurement.vi					
Χ		Χ	NO	SI			DiffDrivePoseEst2_BufferDuration.vi					
Χ	Χ		X				DiffDrivePoseEst2_GetEstimatedPosition.vi					
Χ	Χ	Χ	No				DiffDrivePoseEst2_InterpRecord_ExtractFromVar.vi					
	X	X X	XX	X X X	X X X	X X X	X	X X DiffDrivePoseEst2_GetEstimatedPosition.vi	X         X         X         DiffDrivePoseEst2_AddVisionMeasurement.vi           X         X         NO         SI         DiffDrivePoseEst2_BufferDuration.vi           X         X         X         X         DiffDrivePoseEst2_GetEstimatedPosition.vi	X         X         X         DiffDrivePoseEst2_AddVisionMeasurement.vi           X         X         NO         SI         DiffDrivePoseEst2_BufferDuration.vi           X         X         X         X         X    DiffDrivePoseEst2_GetEstimatedPosition.vi	X         X         X         DiffDrivePoseEst2_AddVisionMeasurement.vi           X         X         NO         SI         DiffDrivePoseEst2_BufferDuration.vi           X         X         X         X         X   DiffDrivePoseEst2_GetEstimatedPosition.vi	X         X         X         DiffDrivePoseEst2_AddVisionMeasurement.vi           X         X         NO         SI         DiffDrivePoseEst2_BufferDuration.vi           X         X         X         X         X    DiffDrivePoseEst2_GetEstimatedPosition.vi

4 2/11/2023 – Added new pose est2		$\overline{}$								
		Χ		No			DiffDrivePoseEst2_InterpRecord_Interp.vi			
	X	X		No			DiffDrivePoseEst2_InterpRecord_New.vi			
	X	Χ		Χ			DiffDrivePoseEst2_New.vi			
	X	Χ		Χ			DiffDrivePoseEst2_ResetPosition.vi			
	X	Χ		Χ			DiffDrivePoseEst2_SetVisionMeasurementStdDevs.vi			
	X	Χ		Χ			DiffDrivePoseEst2_Update.vi			
	X	Χ		X			DiffDrivePoseEst2_UpdateWithTime.vi			
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EXTENDED KALMAN FILTER	R X	X		X			ExtendedKalmanFilter Correct OnlyUY.vi	$\neg$		
EXTENSES NACINANT IETE	X	X		X			ExtendedKalmanFilter Correct.vi Just a shell, not functional!			
	X	X		X		+	ExtendedKalmanFilter_GetP_Single.vi			
	X	X		X		+	ExtendedKalmanFilter GetP.vi			
	X	X	$\overline{}$	X		+	ExtendedKalmanFilter_GetXHat_Single.vi			
	X	X		X		+	ExtendedKalmanFilter GetXHat.vi			
	X	X	$\overline{}$	X		+	ExtendedKalmanFilter New.vi			
	X	X		X		+	ExtendedKalmanFilter Predict.vi			
	X	X	$\vdash$	X		+	ExtendedKalmanFilter Reset.vi			
	X	X		X		+	ExtendedKalmanFilter SetP.vi			
	X	X		X		+	ExtendedKalmanFilter SetXHat Single.vi			
	X	X		X		+	ExtendedKalmanFilter SetXHat.vi			
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		X		X X X			KalmanFilter_GetK KalmanFilter_GetK_Single.vi KalmanFilter_GetXHat			
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KALMAN FILTER LATENCY COMPENSATOR	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not WPILIB	X Menu Item X X X X X X X X X X X X X X X X X X X	X X X	pple Program	KalmanFilter_GetK KalmanFilter_GetK Single.vi  KalmanFilter_GetXHat  KalmanFilter_GetXHaT_Single  KalmanFilter_Predict.vi  KalmanFilter_Predict.vi  KalmanFilter_Sest.vi  KalmanFilter_SetXHat  KalmanFilter_SetXHat  KalmanFilter_SetXHat  KalmanFilter_SetXHat  KalmanFilter_SetXHat_Single  VI Name  Function Prototype  Notes	8	Test Program	Error Checking
KALMAN FILTER LATENCY COMPENSATOR	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not WPILIB	Menu Item  X X X X X Execution Optimized	X X X	pple Program	KalmanFilter_GetK   KalmanFilter_GetK   Single.vi   KalmanFilter_GetXHat   KalmanFilter_GetXHat   KalmanFilter_GetXHat   KalmanFilter_New.vi   KalmanFilter_Predict.vi   KalmanFilter_Reset.vi   KalmanFilter_SetXHat   KalmanFilter_SetXHat   KalmanFilter_SetXHat   KalmanFilter_SetXHat_Single   VI Name   Function Prototype   Notes	8	Test Program	Error Checking
KALMAN FILTER LATENCY COMPENSATOR	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not WPILIB	X Menu Item X X X X X X X X X X X X X X X X X X X	X X X	pple Program	KalmanFilter_GetK KalmanFilter_GetK Single.vi  KalmanFilter_GetXHat  KalmanFilter_GetXHaT_Single  KalmanFilter_Predict.vi  KalmanFilter_Predict.vi  KalmanFilter_Sest.vi  KalmanFilter_SetXHat  KalmanFilter_SetXHat  KalmanFilter_SetXHat  KalmanFilter_SetXHat  KalmanFilter_SetXHat_Single  VI Name  Function Prototype  Notes	8	Test Program	Error Checking
KALMAN FILTER LATENCY COMPENSATOR	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not WPILIB	X Menu Item X X X X X X X X X X X X X X X X X X X	X X X	pple Program	KalmanFilter GetK Single.vi KalmanFilter GetXHat KalmanFilter GetXHat KalmanFilter GetXHat KalmanFilter GetXHat KalmanFilter New.vi KalmanFilter Predict.vi KalmanFilter Predict.vi KalmanFilter SetXHat KalmanFilter SetXHat KalmanFilter SetXHat KalmanFilter_SetXHat Single  VI Name  VI Name  Function Prototype  Notes  KalmanFilterLatencyComp_AddObserverState.vi KalmanFilterLatencyComp_ApplyPastGlobalMeas_FuncGroup.vi  KalmanFilterLatencyComp_ApplyPastGlobalMeasurement_UKF.vi	8	Test Program	Error Checking
KALMAN FILTER LATENCY COMPENSATOR	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not WPILIB	X Menu Item X X X X X X X X X X X X X X X X X X X	X X X	pple Program	KalmanFilter_GetK KalmanFilter_GetK Single.vi KalmanFilter_GetXHat KalmanFilter_GetXHat KalmanFilter_GetXHat KalmanFilter_Pevoit.vi KalmanFilter_Predict.vi KalmanFilter_Reset.vi KalmanFilter_SetXHat KalmanFilter_SetXHat KalmanFilter_SetXHat KalmanFilter_SetXHat_Single  VI Name Function Prototype Notes  KalmanFilterLatencyComp_AddObserverState.vi KalmanFilterLatencyComp_ApplyPastGlobalMeas_FuncGroup.vi KalmanFilterLatencyComp_ApplyPastGlobalMeasurement_UKF.vi KalmanFilterLatencyComp_FindClosestMeasurement.vi	8	Test Program	Error Checking
KALMAN FILTER LATENCY COMPENSATOR	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not WPILIB	X X X X X X X X X X X X X X X X X X X	X X X	pple Program	KalmanFilter_GetK KalmanFilter_GetXIngle.vi KalmanFilter_GetXHat KalmanFilter_GetXHat KalmanFilter_GetXHat KalmanFilter_Predict.vi KalmanFilter_Predict.vi KalmanFilter_Predict.vi KalmanFilter_SetXHat KalmanFilter_SetXHat KalmanFilter_SetXHat KalmanFilter_SetXHat_Single  VI Name Function Prototype Notes  KalmanFilter_LatencyComp_AddObserverState.vi KalmanFilter_LatencyComp_ApplyPastGlobalMeas_FuncGroup.vi KalmanFilter_LatencyComp_ApplyPastGlobalMeasurement_UKF.vi KalmanFilter_LatencyComp_FindClosestMeasurement_vi KalmanFilter_LatencyComp_FindClosestMeasurement_vi KalmanFilter_LatencyComp_New.vi	8	Test Program	Error Checking
KALMAN FILTER LATENCY COMPENSATOR	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	Not WPILIB	X Menu Item X X X X X X X X X X X X X X X X X X X	X X X	pple Program	KalmanFilter_GetK KalmanFilter_GetK Single.vi KalmanFilter_GetXHat KalmanFilter_GetXHat KalmanFilter_GetXHat KalmanFilter_Pevoit.vi KalmanFilter_Predict.vi KalmanFilter_Reset.vi KalmanFilter_SetXHat KalmanFilter_SetXHat KalmanFilter_SetXHat KalmanFilter_SetXHat_Single  VI Name Function Prototype Notes  KalmanFilterLatencyComp_AddObserverState.vi KalmanFilterLatencyComp_ApplyPastGlobalMeas_FuncGroup.vi KalmanFilterLatencyComp_ApplyPastGlobalMeasurement_UKF.vi KalmanFilterLatencyComp_FindClosestMeasurement.vi	8	Test Program	Error Checking

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MECANUM DRIVE POSE ESTIMATOR				¥ .			MecaDrivePoseEst_AddVisionMeasurement_StdDev.vi					
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	X			No			MecaDrivePoseEst_Kalman_F_Callback.vi					
	X	X		No			MecaDrivePoseEst_Kalman_H_Callback.vi					
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	Χ			Χ			MecaDrivePoseEst_ResetPosition.vi					
	Χ			Χ			MecaDrivePoseEst_SetVisionMeasurementStdDevs.vi					
	Χ			Χ			MecaDrivePoseEst_Update.vi					
	X			X			MecaDrivePoseEst_UpdateWithTime.vi					
	Χ			No			MecaDrivePoseEst_VisionCorrect_Callback.vi					
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	X			X			SwerveDrivePoseEst Kalman F Callback.vi					
	X		+	X			SwerveDrivePoseEst Kalman H Callback.vi					
	X			X			SwerveDrivePoseEst_New.vi					
	X		+	X			SwerveDrivePoseEst_New.vi					
	X			X			SwerveDrivePoseEst_ResetFosition.vi SwerveDrivePoseEst_SetVisionMeasurementStdDevs.vi					
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	X	7		$\overline{X}$	~		SwerveDrivePoseEst2 AddVisionMeasurement.vi					
SWERVE DRIVE POSE ESTIMATOR 2	X		X		SI		SwerveDrivePoseEst2 BufferDuration.vi					
SWERVE DRIVE POSE ESTIMATOR 2				X	٠.		SwerveDrivePoseEst2 GetEstimatedPosition.vi					<del>                                     </del>
SWERVE DRIVE POSE ESTIMATOR 2							SwerveDrivePoseEst2_InterpRecord_ExtractFromVar.vi					
SWERVE DRIVE POSE ESTIMATOR 2	Χ		V				SwerveDrivePoseEst2_InterpRecord_Interp.vi					
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SWERVE DRIVE POSE ESTIMATOR 2	X X X X			No No X			SwerveDrivePoseEst2_InterpRecord_New.vi SwerveDrivePoseEst2_New.vi					
SWERVE DRIVE POSE ESTIMATOR 2	X X X X X			No No X X			SwerveDrivePoseEst2_InterpRecord_New.vi SwerveDrivePoseEst2_New.vi SwerveDrivePoseEst2_ResetPosition.vi					
SWERVE DRIVE POSE ESTIMATOR 2	X X X X X X			No No X X			SwerveDrivePoseEst2_InterpRecord_New.vi SwerveDrivePoseEst2_New.vi SwerveDrivePoseEst2_ResetPosition.vi SwerveDrivePoseEst2_SetVisionMeasurementStdDevs.vi					
SWERVE DRIVE POSE ESTIMATOR 2	X X X X X X X			No No X X X X X			SwerveDrivePoseEst2_InterpRecord_New.vi SwerveDrivePoseEst2_New.vi SwerveDrivePoseEst2_ResetPosition.vi SwerveDrivePoseEst2_SetVisionMeasurementStdDevs.vi SwerveDrivePoseEst2_Update.vi					
SWERVE DRIVE POSE ESTIMATOR 2	X X X X X X			No No X X			SwerveDrivePoseEst2_InterpRecord_New.vi SwerveDrivePoseEst2_New.vi SwerveDrivePoseEst2_ResetPosition.vi SwerveDrivePoseEst2_SetVisionMeasurementStdDevs.vi					

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	X	X	λ			UnscentedKalmanFilter_Correct_OnlyUY.vi					
	X	X	λ	(		UnscentedKalmanFilter_Correct_OnlyUYR.vi					
	X	X	λ	(		UnscentedKalmanFilter_Correct.vi					
	X	X	>	(		UnscentedKalmanFilter_GetP_Single.vi					
	X	X	>	(		UnscentedKalmanFilter_GetP.vi					
	X	X	λ	(		UnscentedKalmanFilter_GetXHat_Single.vi					
	X	X	λ	(		UnscentedKalmanFilter_GetXHat.vi					
	X	X	λ	(		UnscentedKalmanFilter_New_Default.vi					
	X	X	λ	(		UnscentedKalmanFilter_New_FuncGroup.vi					
	X	X	λ	(		UnscentedKalmanFilter_New.vi					
	X	Χ	λ			UnscentedKalmanFilter_Predict.vi					
	X	X	λ	(		UnscentedKalmanFilter_Reset.vi					
	X	X	λ,			UnscentedKalmanFilter_SetP.vi					
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Revision 3.04 2/11/2023 – Added new pose est2 Function Prototype VI Name Notes LINEAR SYSTEM LOOP X X LinearSystemLoop ClampInput.vi X LinearSystemLoop Correct.vi LinearSystemLoop GetClampFunction.vi XX Χ LinearSystemLoop GetController.vi LinearSystemLoop GetError Single.vi XX Χ LinearSystemLoop\_GetError.vi XX Χ XX Χ LinearSystemLoop\_GetFeedForward.vi X X X LinearSystemLoop GetNextR Single.vi Χ LinearSystemLoop GetNextR.vi Χ LinearSystemLoop\_GetObserver.vi XX Χ XX Χ LinearSystemLoop GetU Row.vi LinearSystemLoop GetU.vi  $X \mid X$ Χ LinearSystemLoop\_GetXHat\_Single.vi XX X XX LinearSystemLoop GetXHat.vi Χ LinearSystemLoop New BBB LinearSystemLoop New LinearSystem ClampFunc XX Χ LinearSystemLoop New LinearSystem ClampVal.vi XX Χ LinearSystemLoop New.vi LinearSystemLoop\_Predict.vi XX Χ XX LinearSystemLoop\_Reset.vi Χ LinearSystemLoop\_SetClampFunction.vi LinearSystemLoop SetNextR Some.vi XX LinearSystemLoop\_SetNextR.vi Χ LinearSystemLoop SetXHat Single.vi LinearSystemLoop SetXHat.vi Function Prototype Notes LTV DIFFERENTIAL DRIVE CONTROLLER X LTVDiffDriveCtrl Calculate.vi Χ X LTVDiffDriveCtrl New.vi X X \_TVDiffDriveCtrl Calculate TraiState.vi X LTVDiffDriveCtrl\_Calculate\_SetTolerance.vi XX Χ LTVDiffDriveCtrl Calculate AtReference.vi Not WPILIB Function Prototype Notes LTV UNICYCLE CONTROLLER X X LTVUnicycleCtrl\_AtReference.vi Χ  $X \mid X$ X Χ LTVUnicycleCtrl\_Calculate\_TrajState.vi X X LTVUnicycleCtrl Calculate.vi X X Χ Χ LTVUnicycleCtrl New.vi LTVUnicycleCtrl\_SetEnabled.vi Χ Χ X X LTVUnicycleCtrl SetTolerance.vi '========

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atorSim_Update.vi atorSim_Update.vi atorSim_Update.vi atorSim_WouldHitLowerLimit.vi atorSim_WouldHitLowerLimit.vi atorSim_WouldHitLowerLimit.vi atorSim_WouldHitLowerLimit.vi atorSim_WouldHitLowerLimit.vi atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_WouldHitLowerLimit.vi  atorSim_Would	ElevatorSim_SetState.vi  ElevatorSim_Update.vi  ElevatorSim_UpdateX.vi  ElevatorSim_WouldHitLowerLimit.vi  ElevatorSim_WouldHitUpperLimit.vi					
atorSim_Update.vi extend.  atorSim_UpdateX.vi extend.  atorSim_WouldHitUpperLimit.vi extend.  atorSim_UpdateVextend.  atorSim_UpdateVex	ElevatorSim_Update.vi  ElevatorSim_UpdateX.vi  ElevatorSim_WouldHitLowerLimit.vi  ElevatorSim_WouldHitUpperLimit.vi					
atorSim_UpdateX.vi   extend.   exten	ElevatorSim_UpdateX.vi ElevatorSim_WouldHitLowerLimit.vi ElevatorSim_WouldHitUpperLimit.vi					
atorSim WouldHitUpperLimit.vi atorSim WouldHitUpperLimit.vi  ame  Function Prototype  Notes  Function Prototype  Notes  O  Function Prototype  Notes  O  Function Prototype  Notes  Function Prototype  Function Prototype  Notes  Function Prototype  Notes  Function Prototype  Function Prototype  Notes  Function Prototype  Function Prototype  Function Prototype  Notes  Function Prototype  Function Pro	ElevatorSim_WouldHitLowerLimit.vi  ElevatorSim_WouldHitUpperLimit.vi		extend.			
atorSim_WouldHitLowerLimit.vi	ElevatorSim_WouldHitLowerLimit.vi  ElevatorSim_WouldHitUpperLimit.vi					
ame Function Prototype Notes  FeelSim_Execute.vi heelSim_GetAngularVelocityRPM.vi heelSim_GetCurrentDrawAmps fheelSim_New_LinSys MOI. NoNoise fheelSim_New_LinSys MOI. NoNoise fheelSim_New_LinSys MOI. NoNoise fheelSim_New_MinSys Mol. NoNoise fheelSim_New_MinSys Mol. NoNoise fheelSim_New_MinSys Mol. NoNoise fheelSim_Pack_Model_Params.vi fheelSim_Pack_Model_Params.vi fheelSim_SetIstat.vi fheelSim_SetIstat.vi fheelSim_SetIstat.vi fheelSim_Update.vi	ElevatorSim_WouldHitUpperLimit.vi					
ame Function Prototype Notes O	Program					
Function Prototype  Function Prototype  Notes  Function Prototype  Function Protot	ample Program					
TheelSim_Execute.vi TheelSim_GetAngularVelocityRadPerSec.vi TheelSim_GetAngularVelocityRPM.vi TheelSim_GetCurrentDrawAmps TheelSim_New_LinSys TheelSim_SetInput.vi TheelSim_SetInput.vi TheelSim_SetState.vi TheelSim_Update.vi	w VI Nome			e Review	Program	r Checking
TheelSim_Execute.vi TheelSim_GetAngularVelocityRadPerSec.vi TheelSim_GetAngularVelocityRPM.vi TheelSim_GetCurrentDrawAmps TheelSim_New_LinSys TheelSim_SetInput.vi TheelSim_SetInput.vi TheelSim_SetState.vi TheelSim_Update.vi		F " B		900	est	ē
Indee Sim_GetAngularVelocityRadPerSec.vi		Function Prototype	Notes	<u>`</u>	<u> </u>	<u>W</u>
IndeelSim_GetAngularVelocityRPM.vi   IndeelSim_GetCurrentDrawAmps   IndeelSim_New_LinSys   IndeelSim_New_LinSys   IndeelSim_New_LinSys   IndeelSim_New_LinSys   IndeelSim_New_LinSys   IndeelSim_New_LinSys   IndeelSim_New_LinSys   IndeelSim_New_LinSys   IndeelSim_New_Mol.vi   IndeelSim_Pack_Model_Params.vi   IndeelSim_Pack_Model_Params.vi   IndeelSim_SetInput.vi   IndeelSim_SetState.vi   IndeelSim_Update.vi   Indee					.——	
IntelSim_GetCurrentDrawAmps	FlyWheelSim_GetAngularVelocityRadPerSec.vi					
Future   F	FlyWheelSim_GetAngularVelocityRPM.vi					
VineelSim_New_LinSys_MOI_NoNoise VineelSim_New_LinSys_NoNoise VineelSim_New_MOI.vi VineelSim_Pack_Model_Params.vi VineelSim_SetInput.vi VineelSim_SetState.vi VineelSim_Update.vi	HyWheelSim_GetCurrentDrawAmps					
//heelSim_New_LinSys_NoNoise						
//heelSim_New_MOI.vi //heelSim_Pack_Model_Params.vi //heelSim_SetInput.vi //heelSim_SetState.vi //heelSim_Update.vi	FlyWheelSim_New_LinSys_MOI_NoNoise					
//heelSim_Pack_Model_Params.vi //heelSim_SetInput.vi //heelSim_SetState.vi //heelSim_Update.vi			Future			
//heelSim_SetInput.vi //heelSim_SetState.vi //heelSim_Update.vi						
/heelSim_SetState.vi /heelSim_Update.vi						
/heelSim_Update.vi						
	FlyWheelSim_SetState.vi					
	FlyWheelSim Update.vi					
Programmer Control of the Control of	igram					
est eest	ample Pro	5 × 5 × 1	N	ode Review	est Program	rror Checking
ame Function Prototype Notes O H iii	ର	Function Prototype	Notes	Code Review	Test Program	Error Checking
ame Function Prototype Notes O Function Prototype arSystemSim_ClampInput.vi	VI Name  LinearSystemSim_ClampInput.vi	Function Prototype		Code Review	Test Program	Error Checking
ame Function Prototype Notes 0 1 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi	Function Prototype		Code Review	Test Program	Error Checking
Function Prototype  Notes  Function Prototype  Notes  O  Function Prototype  Notes  O  Function Prototype  DONT IMPLEMENT  ArSystemSim_GetCurrentDrawAmps.vi  ArSystemSim_GetOutput_Single.vi	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi	Function Prototype		Code Review	Test Program	Error Checking
Function Prototype  Notes  Function Prototype  Notes  O  Function Prototype  O	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi  LinearSystemSim_GetOutput.vi	Function Prototype		Code Review	Test Program	Error Checking
Function Prototype  Notes  Function Prototype  Notes  O  Function Prototype  O  Function Prototype  Notes  O  Function Prototype  O  Function	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi  LinearSystemSim_GetOutput.vi  LinearSystemSim_New	Function Prototype		Code Review	Test Program	Error Checking
Function Prototype  Notes  Function Prototype  Notes  O  Function Prototype  D  O  Function Prototype  D  O  Function Prototype  D  O  Function Prototype  O  Function Prototype  Notes  O  Function Prototype  Notes  O  Function Prototype  Notes  O  Function Prototype  Notes  O  Function Prototype  O  Function Prototype  Notes  O  Function Prototype  O  Function Prototype  O  Function Prototype  Notes  O  Function Prototype	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi  LinearSystemSim_GetOutput.vi  LinearSystemSim_New  LinearSystemSim_New  LinearSystemSim_New_NoNoise.vi	Function Prototype	DONT IMPLEMENT	Code Review	Test Program	Error Checking
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Function Prototype  Function Prototype  Notes  Function Prototype  Function Prototype  Notes  Function Prototype  Function Prototype  Notes  Function Prototype  Function Prototype  Notes  Function Prototype  Functio	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi  LinearSystemSim_GetOutput.vi  LinearSystemSim_New  LinearSystemSim_New_NoNoise.vi  LinearSystemSim_SetInput_Array.vi  LinearSystemSim_SetInput_Single.vi	Function Prototype	DONT IMPLEMENT	Code Review	Test Program	Error Checking
Function Prototype  Function Prototype  Notes  Function Prototype  Function Prototype  Notes  Function Prototype  Function Prototype  Notes  Function Prototype  Notes  Function Prototype  Functio	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi  LinearSystemSim_GetOutput.vi  LinearSystemSim_New  LinearSystemSim_New_NoNoise.vi  LinearSystemSim_SetInput_Array.vi  LinearSystemSim_SetInput_Single.vi  LinearSystemSim_SetInput_Single.vi	Function Prototype	DONT IMPLEMENT	Code Review	Test Program	Error Checking
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Function Prototype  Function Prototype  Notes  Function Prototype	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi  LinearSystemSim_GetOutput.vi  LinearSystemSim_New  LinearSystemSim_New_NoNoise.vi  LinearSystemSim_SetInput_Array.vi  LinearSystemSim_SetInput_Single.vi  LinearSystemSim_SetInput_Vi  LinearSystemSim_SetInput.vi  LinearSystemSim_SetInput.vi  LinearSystemSim_SetInput.vi  LinearSystemSim_SetInput.vi  LinearSystemSim_SetInput.vi  LinearSystemSim_Update.vi	Function Prototype	DONT IMPLEMENT	Code Review	Test Program	Error Checking
Function Prototype  Function Prototype  Notes  Function Prototype  Notes  Function Prototype  Notes  Function Prototype  Notes  Function Prototype  DONT IMPLEMENT  DONT IMPLEMENT  Function Prototype  Function Prototype  DONT IMPLEMENT  Function Prototype  Funct	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi  LinearSystemSim_GetOutput.vi  LinearSystemSim_New  LinearSystemSim_New_NoNoise.vi  LinearSystemSim_SetInput_Array.vi  LinearSystemSim_SetInput_Single.vi  LinearSystemSim_SetInput_Single.vi  LinearSystemSim_SetInput.vi  LinearSystemSim_SetInput.vi  LinearSystemSim_SetInput.vi	Function Prototype	DONT IMPLEMENT	Code Review	Test Program	Error Checking
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ode est	ample Pro			ode Review	est Program	rror Checking
Time Function Prototype Notes O L L	S NI Name อัต ภัก	Function Prototype	Notes	Code Review	Test Program	Error Checking
ame Function Prototype Notes O H iii	ର	Function Prototype	Notes	Code Review	Test Program	Error Checking
ame Function Prototype Notes O Function Prototype arSystemSim_ClampInput.vi	VI Name  LinearSystemSim_ClampInput.vi	Function Prototype		Code Review	Test Program	Error Checking
ame Function Prototype Notes O Function Prototype arSystemSim_ClampInput.vi	VI Name  LinearSystemSim_ClampInput.vi	Function Prototype		Code Review	Test Program	Error Checking
ame Function Prototype Notes 0 1 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi	Function Prototype		Code Review	Test Program	Error Checking
ame Function Prototype Notes 0 1 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2 2	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi	Function Prototype		Code Review	Test Program	Error Checking
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Function Prototype  Notes  Function Prototype  Notes  O  Function Prototype  Notes  O  Function Prototype  DONT IMPLEMENT  ArSystemSim_GetCurrentDrawAmps.vi  ArSystemSim_GetOutput_Single.vi	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi	Function Prototype		Code Review	Test Program	Error Checking
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Function Prototype  Notes  Function Prototype  Notes  O  Function Prototype  O	VI Name  LinearSystemSim_ClampInput.vi  LinearSystemSim_GetCurrentDrawAmps.vi  LinearSystemSim_GetOutput_Single.vi  LinearSystemSim_GetOutput.vi	Function Prototype		Code Review	Test Program	Error Checking
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-	l est Koutine	FlyWheelSim_GetAngularVelocityRPM.vi FlyWheelSim_GetCurrentDrawAmps FlyWheelSim_New_LinSys FlyWheelSim_New_LinSys_MOI_NoNoise FlyWheelSim_New_LinSys_NoNoise FlyWheelSim_New_MOI.vi FlyWheelSim_Pack_Model_Params.vi FlyWheelSim_SetInput.vi FlyWheelSim_SetState.vi FlyWheelSim_Update.vi	FlyWheelSim_GetAngularVelocityRPM.vi FlyWheelSim_GetCurrentDrawAmps FlyWheelSim_New_LinSys FlyWheelSim_New_LinSys_MOI_NoNoise FlyWheelSim_New_LinSys_NoNoise FlyWheelSim_New_MOI.vi FlyWheelSim_Pack_Model_Params.vi FlyWheelSim_SetInput.vi FlyWheelSim_SetState.vi FlyWheelSim_Update.vi	FlyWheelSim_GetAngularVelocityRPM.vi FlyWheelSim_GetCurrentDrawAmps FlyWheelSim_New_LinSys FlyWheelSim_New_LinSys_MOI_NoNoise FlyWheelSim_New_LinSys_NoNoise FlyWheelSim_New_LinSys_NoNoise FlyWheelSim_New_MOI.vi FlyWheelSim_Pack_Model_Params.vi FlyWheelSim_SetInput.vi FlyWheelSim_SetState.vi	FlyWheelSim_GetAngularVelocityRPM.vi FlyWheelSim_GetCurrentDrawAmps FlyWheelSim_New_LinSys FlyWheelSim_New_LinSys_MOI_NoNoise FlyWheelSim_New_LinSys_NoNoise FlyWheelSim_New_LinSys_NoNoise FlyWheelSim_New_MOI.vi FlyWheelSim_Pack_Model_Params.vi FlyWheelSim_SetInput.vi FlyWheelSim_SetState.vi	FlyWheelSim_GetAngularVelocityRPM.vi FlyWheelSim_GetCurrentDrawAmps FlyWheelSim_New_LinSys FlyWheelSim_New_LinSys_MOI_NoNoise FlyWheelSim_New_LinSys_MOI_NoNoise FlyWheelSim_New_LinSys_NoNoise FlyWheelSim_New_LinSys_NoNoise FlyWheelSim_New_MOI.vi FlyWheelSim_Pack_Model_Params.vi FlyWheelSim_SetInput.vi FlyWheelSim_SetState.vi

X	Χ		Χ		SngJntArmSim_GetVelocityRadsPerSec.vi
X	Χ		Χ		SngJntArmSim_HasHitLowerLimit.vi
X	Χ		X		SngJntArmSim_HasHitUpperLimit.vi
X	Χ		Χ		SngJntArmSim_New.vi
X		Χ			SngJntArmSim_Pack_Model_Params.vi
X		Х			SngJntArmSim_Pack_Simulation_Params.vi
X	Χ		No		SngJntArmSim_Rkf45_Func.vi
X	Χ		X		SngJntArmSim_SetInputVoltage.vi
X	Χ		X		SngJntArmSim_SetState.vi
X	Χ		Χ		SngJntArmSim_Update.vi
X	Χ		X		SngJntArmSim_UpdateX.vi
X	Χ		Χ		SngJntArmSim_WouldHitLowerLimit.vi
X	Χ		Χ		SngJntArmSim_WouldHitUpperLimit.vi

'======= MATRIX UTILITIES '=======

> Function Prototype MAT BUILDER X X X X X X MatBuilder\_Create.vi
> MatBuilder\_Fill.vi X SI X SI

Implemented		Documented Not WPILIB		Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
MATRIX $X$	<b>(</b>	X	X	SI			Matrix_AssignBlock.vi					
X	(	X	X	SI			Matrix_Block.vi					
							Matrix_ChangeBoundsUnchecked.vi					
X	<b>(</b>	X	X	SI			Matrix_Create.vi					
							Matrix_Det.vi					
X	<b>(</b>	X	X	SI			Matrix_Diag.vi					
							Matrix_Div_Scalar.vi		labview has function			
							Matrix ElementPower.vi					
X	<b>7</b>	X	X	SI			Matrix ElementSum.vi					
							Matrix ElementTimes.vi					
							Matrix Equals.vi					
X	<b>(</b>	X	X	1			Matrix Exp.vi					
X	<	X	X	SI			Matrix ExtractColumnVector.vi					
X	<b>(</b>	X	X	SI			Matrix_ExtractFrom.vi					
							Matrix_ExtractMatrix.vi					
X	<b>(</b>	X	X	SI			Matrix_ExtractRowVector.vi					
X	(	X	X	SI			Matrix_Fill.vi					
							Matrix_Get.vi		labview has function			
X	(	X	X	1			Matrix_Ident.vi		WPILIB calls this EYE			
							Matrix_Inv.vi					
X	(	X	X	SI			Matrix_IsEqual.vi					
							Matrix_IsIdentical.vi					
X	(	X	X	I			Matrix_LLTDecompose.vi					
							Matrix_Max.vi					
							Matrix_MaxAbs.vi					
							Matrix_Mean.vi					
							Matrix_MinInternal.vi					
							Matrix_Minus_Matrix.vi					
							Matrix_Minus_Scalar.vi					
X	<b>〈</b>	X	X	I			Matrix_NormF.vi					
							Matrix_NormIndP1.vi					
							Matrix_Plus_Matrix.vi					
							Matrix_Plus_Scalar.vi					

X	pose est2							· · · · · · · · · · · · · · · · · · ·				
Mark					Χ	1		Matrix_Pow.vi	THIS NEEDS WORK!!!!			
Mark					X							
		X	X		X	SI		Matrix_SetRow.vi THERE ARE LOTS OF OTHER MATRIX FUNCTIONS THAT				
More   Imes Season   More   Imes Season   More   Imes Season   More								Matrix Solve vi				
Mark Trible								Matrix Times Matrix vi				
MATRIX HELPER   MATRIX   X   X   X   X   X   X   X   X   X												
Marrier   Marr		X	X		X	SI		Matrix Transpose vi				
SIMPLE MATRIX   X   X   X   X   X   X   X   X   X				X	X			Matrix Within Tolerance vi				
SIMPLE MATRIX   X   X   X   X   X   X   X   X   X												
VECTOR BUILDER   X   X   X   S     MatrixHelper Zero.vi		X Implemented X	X Documented	X Not WPILIB	X Menu Item	© Execution Optimized ©		SimpleMatrix_ExtractMatrix.vi  VI Name  Function Prototype  MatrixHelper_CooerceSize.vi	NOTE Matrix also has an ExtractMatrix with different calling parameters YUK.			Error Checking
VECTOR BUILDER   X   X   X   S     MatrixHelper Zeroxi	WAIRIA HELPER				~							
Part		X V	X V	- X	Λ ∨	SI SI		MatrixHelper_MultCooercepSize.vi				
VecTor Builder   X		mplemented	<i><b>Documented</b></i>	Vot WPILIB	Jenu Item		Fest Routine	VI Name Function Prototype	Notes	Sode Review	Fest Program	Error Checking
X	VECTOR BUILDER						<u> </u>				-	
X												
X		X	X		X	SI						
X		X	X		X	SI						
X		Χ	X		X	SI						
X		X	X		X	SI		VecBuilder 6x1Fill.vi				
X			X		X	SI						
VecBuilder_9x1Fill.vi		X	X		X	SI						
VecBuilder_10x1Fill.vi								VecBuilder_9x1Fill.vi				
X								VecBuilder_10x1Fill.vi				
VECTOR   X   X   X   SI   Vector_Dot.vi   Ve		Х	X	Χ	X	SI		VecBuilder_ArrayBy1Fill.vi				
Tig tig 1         Lig tig 1 <t< td=""><td></td><td></td><td></td><td></td><td></td><td></td><td></td><td></td><td></td><td></td><td></td><td></td></t<>												
VECTOR X X X S/ Vector_Dot.vi		mplemented	Documented	Jot WPILIB	Aenu Item	Execution Optimized	est Routine	VI Name  Function Prototyne	Notes	Sode Review	est Program	error Checking
	VEGTOR	<u>×</u> _					<u> </u>		NUCES	U U		ш
A A A SI VECIO_NOTTILVI	VECTOR					Si Si		Vector Norm vi				
		_ X	X		X	SI		Vector_INOTHI.VI				
		1	1		1					l	I	

ANGLE STATISTICS	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	X Not WPILIB	X X X X X X X X X X X X X X X X X X X	I X	X Test Routine	VI Name  AngleStats AngleAdd CallbackHelp.vi  AngleStats AngleAdd.vi  AngleStats AngleMean CallbackHelp.vi  AngleStats AngleMean.vi  AngleStats AngleResidual CallbackHelp.vi  AngleStats AngleResidual.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
MATH UTILITY	X X X X X X X X X X X X X X X X X X X	X X X X X X	Not WPILIB	X X X X X X	S S S Execution Optimized	Test Routine	VI Name  MathUtil_AngleModulus.vi  MathUtil_ApplyDeadband.vi  MathUtil_Clamp_Int.vi  MathUtil_Clamp.vi  MathUtil_InputModulus.vi  MathUtil_Interpolate.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
MERWE SCALED SIGMA POINTS	X X Implemented	X X X X X X X X X X X X X X X X X X X	Not WPILIB	X X X X X X X X X X X X X X X X X X X	SI SI SI I	Test Routine	VI Name  MerweScSigPts_ComputeWeights.vi  MerweScSigPts_GetNumSigmas.vi  MerweScSigPts_GetWc_Single.vi  MerweScSigPts_GetWc.vi  MerweScSigPts_GetWm_Single.vi  MerweScSigPts_GetWm.vi  MerweScSigPts_New_Default.vi  MerweScSigPts_New.vi  MerweScSigPts_SigmaPoints.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
NUMERICAL INTEGRATION	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X		No No No			VI Name NumIntegrate_Func_Ax_Bu_K.vi NumIntegrate_Rk4_Dbl_X_U.vi NumIntegrate_Rk4_Dbl_X.vi NumIntegrate_Rk4_Mat_X_U.vi NumIntegrate_Rk4_Mat_X.vi NumIntegrate_Rk4_Mat_X.vi NumIntegrate_Rkdp_Func_A.vi NumIntegrate_Rkdp_Func_B1.vi NumIntegrate_Rkdp_Func_B1B2.vi NumIntegrate_Rkdp_Func_B2.vi NumIntegrate_Rkdp_Func_B2.vi NumIntegrate_Rkdp_Impl.vi	Function Prototype	Notes NOT USED. Should this be used or abandoned???	Code Review	Test Program	Error Checking

	X	X		No	SI		NumIntegrate_Rkf45_Func_A.vi					
	Χ	Χ		No	SI		NumIntegrate_Rkf45_Func_B1.vi					
	Χ	X		No	SI		NumIntegrate_Rkf45_Func_B1B2.vi					
	Χ	X		No	SI		NumIntegrate_Rkf45_Func_B2.vi					
			,				NumIntegrate_RKf45_Func_Bs.vi		Removed. Replaced with newer			
			$\dashv$				NumIntegrate_RKf45_Func_Ch.vi		functions.  Removed. Replaced with newer			
							NumIntegrate_RKf45_Func_Ct.vi		functions.  Removed. Replaced with newer			
									functions.			
	X	X		No X	1		NumIntegrate_Rkf45_Impl.vi NumIntegrate_Rkf45_Mat_X_U.vi		Note that this Feinberg method has been changed and a Dormand Price method has been			
			$\rightarrow$				NumIntegrate_RKf45_New.vi		implemented TODO Removed. Never used.			
	Χ	Χ	X	Χ	SI		NumIntegrate_Trap_Dbl.vi					
	X	X	X	Χ	1		NumIntegrate_Trap_Mat.vi					
UNGE KUTTA TIME VARYING	X Implemented	X Documented	Not WPILIB	S Menu Item	Execution Optimize	Test Routine Sample Program	VI Name   RungeKuttaTimeVarying_RK4_Mat_T_Y.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
NUMERICAL JACOBIAN		Χ		Χ			NumJacobian_U.vi					
	Χ	Χ		Χ			NumJacobian_X.vi					
	þe	Pe	8		tion Optimized	utine				~	am Wa	hecking
RICCATI	X X X X X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X		X X X X X X X X X X X X X X X X X X X	Execu	X X Test Routine Sample Prog	<b>X</b>	Function Prototype	Notes  Routine exists, it is just a shell  Not really done !!!  Intended to allow DARE method testing.	Code Review	Test Progr	Error C
RICCATI	X X X X X	X X X X X	Not W	X X X X X X	ized	X X X X X X X X X X X X X X X X X X X	VI Name  Riccati_Check_Detectable.vi  Riccati_Check_Stabilizable.vi  Riccati_DARE_Choose.vi  Riccati_DARE_Iterate.vi  Riccati_DARE_StructDoubling.vi  Riccati_DARE_N.vi  Riccati_DARE.vi  Riccati_Input_Check.vi	Function Prototype	Routine exists, it is just a shell Not really done !!! Intended to allow DARE method		Test Progr	. Error C
RICCATI	X X X X X	X X X X X	X X X	X X X X X X	Execu	X X X Sample	VI Name  Riccati_Check_Detectable.vi  Riccati_Check_Stabilizable.vi  Riccati_DARE_Choose.vi  Riccati_DARE_Iterate.vi  Riccati_DARE_StructDoubling.vi  Riccati_DARE_N.vi  Riccati_DARE.vi  Riccati_Input_Check.vi	Function Prototype  Function Prototype	Routine exists, it is just a shell Not really done !!! Intended to allow DARE method		Test Program  Test Program	Error Checking
RICCATI	Implemented X X X X Implen	X X X X X	Not W	X	Optimized	X X X X X X X X X X X X X X X X X X X	VI Name  Riccati_Check_Detectable.vi  Riccati_Check_Stabilizable.vi  Riccati_DARE_Choose.vi  Riccati_DARE_Iterate.vi  Riccati_DARE_StructDoubling.vi  Riccati_DARE_N.vi  Riccati_DARE.vi  Riccati_Input_Check.vi		Routine exists, it is just a shell Not really done !!! Intended to allow DARE method testing.	Review Code !	Program	ror Checking

'======= VISION '========

X   X	X		CompVisionUtil_EstimateFieldToCamera.vi		
XX	X		CompVisionUtil_EstimateFieldToRobot.vi		
XX	X		CompVisionUtil_EstimateFieldToRobot_Alt.vi		
XX	X		CompVisionUtil_ObjectToRobotPose.vi		
		_			
		be.			
		٧.	-		

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimize	Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
APRIL TAG	X	Χ		Χ	SI		AprilTag_Equals.vi					
	Χ	X	X	Χ	SI		AprilTag_GetAll.vi					
	X	Χ		Χ	SI		AprilTag_New.vi					
APRIL TAG	X	Х		X	SI		AprilTag_Equals.vi AprilTag_GetAll.vi AprilTag_New.vi	. a.c.s rowypo				

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optir	Test Routine	Sample Prograi	Function Prototype	Notes	Code Review	Test Program	Error Checking
APRIL TAG FIELD LAYOUT	X	Χ		X	SI		AprilTagFieldLayout_GetField.vi					
	Χ	Χ		X	SI		AprilTagFieldLayout_GetOriginPosition.vi					
	X	Χ		X	SI		AprilTagFieldLayout_GetTagPose.vi					
	Χ	Χ		X	SI		AprilTagFieldLayout_GetTags.vi					
	Χ	Χ		Χ	SI		AprilTagFieldLayout_New.vi					
	Χ	Χ		X	SI		AprilTagFieldLayout_New2022.vi					
	Χ	Χ		Χ	SI		AprilTagFieldLayout_New2023.vi					
	Χ	Χ		X	SI		AprilTagFieldLayout_NewSelect.vi					
	X	Χ		Χ	SI		AprilTagFieldLayout_SetOrigin.vi					
	Χ	Χ		X	SI		AprilTagFieldLayout_SetOrigin_Position.vi					

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
APRIL TAG POSE ESTIMATE	Χ	Χ		Χ	SI		AprilTagPoseEstimate_GetAll.vi					
	Χ	Χ		Χ	SI		AprilTagPoseEstimate_GetAmbiguity.vi					
	Χ	Χ		Χ	SI		AprilTagPoseEstimate_New.vi					

'======== COMMUNICATIONS '========

> | NETMORK AND | NAORUMENTED | Function Prototype Notes VI Name NetworkUDP\_Close.vi NetworkUDP\_Receive.vi
> NetworkUDP\_Send.vi

'======== TYPE DEFINITIONS

Revision 3.04	2/11/2023 -	Added new	pose est
'=======			

Implemented		Documented	Not WPILIB	Menu Item	Execution Optimize	Test Routine	ample Program	VI Name	Function Prototype	Notes
ef Z		Z	X	_ <b>∠</b>		_		AprilTag.ctl	Function Frototype	Notes
Z		Z	X	X				AprilTagFieldLayout,ctl		
Z	_	Z	X	X				AprilTagFieldLayoutOriginPosition_ENUM.ctl		
Z	-	Z	X	X				AprilTagFields ENUM.ctl		
Z	_	Z	X	X				AprilTagPoseEstimate.ctl		
Z	_	$\frac{z}{z}$	X	X				ARM FF.CTL		
Z		Z	X	X				BANG BANG.CTL		
1			X	X				BICon-Matrix_FUNC_TYPE.CTL		NOT USED. Should this be deleted or abandoned???
Ζ		Ζ	Χ	Χ				CALLBACK_FUNC_TYPE.CTL		
Z		Ζ	Χ	Χ	N/A			CHASSIS_SPEEDS.CTL		
Z		Ζ	Χ		N/A			CONTRAINED_STATE.CTL		
Z		Ζ	Χ		N/A			COORDINATE_AXIS.CTL		
Z		Ζ	Χ		N/A			COORDINATE_SYSTEM.CTL		
Z	_	Ζ	Χ	Χ	N/A			DCMOTOR_SIM.CTL		
Z	_		Z		N/A			DCMOTOR_SIM_MODEL_PARAMS.CTL		
	_	Z	X		N/A			DCMOTOR_TYPES_ENUM.CTL		
Z	-	Z	X		N/A			DCMOTOR.CTL		
Z	_	Z	X		N/A			DEBOUNCER_TYPE_ENUM.Ctl		
	_	Z	X	X	N/A			DEBOUNCER.CTL		
Z	_	Z	Χ	X				DIFF_DRIVE_ACCEL_LIMIT.CTL		
Z		Z	X	X				DIFF_DRIVE_KINEMATICS.CTL		
Z		Z	X		N/A			DIFF_DRIVE_Kitbot_WheelSize_ENUM.ctl		
Z		Z	X		N/A			DIFF_DRIVE_ODOM2.ctl		
	_	Z	Χ	X				DIFF_DRIVE_Pose_EST.ctl		
Z			X	X				DIFF_DRIVE_POSE_EST2.ctl		
Z	_	-	X		N/A			DIFF_DRIVE_POSE_EST2_INTERP_RECORD.CTL		
	-	Z	X	X	N/A N/A			DIFF_DRIVE_ToughBoxMini_GearChoice_ENUM.ctl		
Z	_	Z						DIFF_DRIVE_ToughBoxMini_MotorChoice_ENUM.ctl		
	_	Z	X	X				DIFF_DRIVE_TRAIN_SIM_STATE_ENUM.CTL DIFF_DRIVE_TRAIN_SIM.ctl		
Z	-	Z Z	X	X				DISPLAY WAYPOINT.ctl		Was UTIL_WAYPOINT.VI
Z	_	Z	X	X				DISPLAY_WEIGHTED_WAYPOINT.ctl		New V1.5. was UTIL_WEIGHTED_WAYPOINIT.V
Z		Ζ	Χ	X	N/A			ELEV FF.CTL		
Z		Ζ	X	X	N/A			ELEVATOR SIM.CTL		
Z			Ζ		N/A			ELEVATOR_SIM_MODEL_PARAMS.CTL		
Z			Z		N/A			ELEVATOR_SIM_SIMULATION_PARAMS.CTL		
Z		Ζ	Χ	X	N/A			EXTENDED_KALMAN_CORRECT_FUNC_GROUP.CTL		
Z			Χ	X	N/A			EXTENDED_KALMAN_FILTER.CTL		
Z	'	Ζ	Χ	Χ	N/A			FLYWHEEL_SIM.ctl		
Z	_		Ζ		N/A			FLYWHEEL_SIM_MODEL_PARAMS.CTL		
Ζ		Ζ	Χ		N/A			FUNCTION_GENERATOR_MATRIX.ctl		
Z	_	Ζ	Χ		N/A			FUNCTION_GENERATOR.ctl		
Z		Ζ	Χ		N/A			HOLONOMIC_DRV_CTRL.CTL		New 1/26/21
Ζ		Ζ	Χ		N/A			KALMAN_FILTER_LATENCY_COMP_FUNC_GROUP.CTL		
Z		Ζ	Χ		N/A			KALMAN_FILTER_LATENCY_COMP.CTL		
Z	_	Z	Χ		N/A			KALMAN_FILTER.ctl		
Z		Ζ	Χ	Χ	N/A			LINEAR_FILTER.CTL		
Z		Ζ	Χ		N/A			LINEAR_PLANT_INV_FF.ctl		
Z		Z	X		N/A			LINEAR_QUADRATIC_REGULATOR.ctl		
Z		Z	X		N/A			LINEAR_SYSTEM_LOOP.ctl		
<u>Z</u>		Z	Χ		N/A			LINEAR_SYSTEM_SIM.ctl		
<u>Z</u>		Z	X		N/A			LINEAR_SYSTEM.ctl		
Z		Z	Χ		N/A			LTV_DIFF_DRIVE_CTRL_STATE_ENUM.ctl		
Z		Ζ	X	X	N/A			LTV_DIFF_DRIVE_CTRL.ctl		
N/A	_	_	N/A		N/A			LTV_UNICYCLE_CONTROLLER_INPUT_ENUM.ctl		OBSOLETE – Removed
Z		Z	X		N/A			LTV_UNICYCLE_CONTROLLER_STATE_ENUM.ctl		
Z		Z	X		N/A			LTV_UNICYCLE_CONTROLLER.CTL		
Z		Z	Χ		N/A			MECA_DRIVE_KINEMATICS.CTL		
	'	Ζ	Χ	X	N/A			MECA_DRIVE_ODOMETRY.CTL		

Z	Ζ	X .	X N/A	MECA DRIVE POSE EST.CTL	
Z	Z		X N/A	MECA WHEEL POSITIONS.CTL	
Z	Z		X N/A	MECA WHEEL SPEEDS.CTL	
Z	Z		X N/A	MEDIAN FILTER.CTL	
Z	Z		$\frac{X}{X} = \frac{N/A}{N/A}$	MERWE SCALED SIGMA PTS.ctl	
Z	Z		$\frac{X}{X} = \frac{N/A}{N/A}$	OBSERVER SNAP LIST ITEM.CTL	
Z	Z			OBSERVER_SNAPSHOT.CTL	
Z	Z		X N/A	PARAM_STACK_ITEM.CTL	
Z	Z		X N/A	PARAM_STACK.CTL	
Z	Ζ		X N/A	PID_ADV_LIMITS.CTL	
Z	Ζ		X N/A	PID_ADV_TUNING.CTL	
Ζ	Ζ		X N/A	PID_CONTROLLER.CTL PID_CONTROLLER.CTL	
Z	Z	X   .	X N/A	PID_ERROR_TOLERANCE.CTL	
Z	Z	X .	X N/A	PID INPUT LIMITS.CTL	
Z	Ζ	X .	X N/A	PID TUNING.CTL	
Z	Ζ		X N/A	POSE2D.CTL	
Z	Ζ		X N/A	POSE3D.CTL	
Z	Z		X N/A	POSEwCURVATURE.CTL	
Z	Z		X N/A	PROFILED PID CONTROLLER.CTL	
Z	Z		X N/A	QUATERNION.CTL	
Z	Z				
	Z		X N/A X N/A	RAMSETE_EXE_TUNING.CTL  RAMSETE.CTL	
Z					
Z	Z	X .	X N/A	ROTATION2D.CTL	
Z	Z		X N/A	ROTATION3D.CTL	
Z	Ζ	X	N/A	SIMPLE_MOTOR_FF_KA_TUNE_PARAMS.CTL	
Z	Ζ		X N/A	SIMPLE_MOTOR_FF.CTL	
Z	Ζ		X N/A	SINGLE_JOINT_ARM_SIM.CTL	
Z		Х	N/A	SINGLE_JOINT_ARM_SIM_MODEL_PARAMS.CTL	
Z		X	N/A	SINGLE JOINT ARM SIM SIMULATION PARAMS.CTL	
Ζ	Ζ	X .	X N/A	SLEW RATE LIMITER.CTL	
Z	Ζ		X N/A	SPLINE CTRL VECTOR.CTL	
Z	Z		X N/A	SPLINE.CTL	
Z	Z		X N/A	SWERVE DRIVE KINEMATICS.CTL	
Z	Z		X N/A	SWERVE DRIVE MODULE POSITION.CTL	
Z	Z		$\frac{X}{X} \frac{N/A}{N/A}$	SWERVE_DRIVE_MODULE_STATE.CTL	
Z	Z			SWERVE_DRIVE_MODULE_STATE.CTL SWERVE DRIVE ODOMETRY.CTL	
Z	Ζ		X N/A	SWERVE_DRIVE_Pose_EST.CTL	
Z		X .	X N/A	SWERVE DRIVE POSE EST2.ctl	
Z	_	ΧN	Vo N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL	
Ζ	Z	X N	Vo N/A X N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL	
Z	Ζ	X N X .	Vo N/A X N/A X N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL TIME_INTERPOLATABLE_DOUBLE.CTL	
Ζ	Z Z	X N X X	\( \lambda \) \(	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL	
Z	Ζ	X N X X	Vo N/A X N/A X N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL TIME_INTERPOLATABLE_DOUBLE.CTL	
Z Z Z	Z Z	X N X X	\( \lambda \) \(	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL	
Z Z Z Z	Z Z Z	X N X X X X	No         N/A           X         N/A           X         N/A           X         N/A           X         N/A           X         N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL	
Z Z Z Z	Z Z Z Z	X	No N/A X N/A X N/A X N/A X N/A X N/A N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL	
Z Z Z Z Z	Z Z Z Z	X	No N/A X N/A X N/A X N/A X N/A X N/A X N/A N/A X N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL	
Z Z Z Z Z Z Z	Z Z Z Z Z Z	X	No N/A X N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_CCTL  TRAJ_CONFIG.CTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL	
Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z	X	\text{NO} \text{ N/A}	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIMER.CTL  TRAJ_CONFIG.CTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL	
Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	X N X X X X X X X X X X X X X X X X X X	\( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \)	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_CCTL  TRAJ_CONFIG.CTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL	
Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z	X	NO	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIMER.CTL  TRAJ_CONFIG.CTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL  TRAJ_CONSTRAINT_ELLIP_REGION.CTL	Routine exists it is just a shell
Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	X	\( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \)	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIMER.CTL  TRAJ_CONFIG.CTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL  TRAJ_CONSTRAINT_ELLIP_REGION.CTL  TRAJ_CONSTRAINT_JERK.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	X	\text{NO} \text{ N/A}	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIMER.CTL  TRAJ_CONFIG.CTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL  TRAJ_CONSTRAINT_ELLIP_REGION.CTL  TRAJ_CONSTRAINT_JERK.CTL  TRAJ_CONSTRAINT_JERK.CTL  TRAJ_CONSTRAINT_JERK.CTL	Routine exists, it is just a shell
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Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	X	\( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \)	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIMER.CTL  TRAJ_CONFIG.CTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL  TRAJ_CONSTRAINT_BLLIP_REGION.CTL  TRAJ_CONSTRAINT_JERK.CTL  TRAJ_CONSTRAINT_MAX_VELOCITY.CTL  TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_MINMAX.CTL	Routine exists, it is just a shell
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Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z		N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL TIME_INTERPOLATABLE_DOUBLE.CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_ROTATION2D.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIMER.CTL TRAJ_CONSTG.CTL TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_ELLIP_REGION.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJ_STATE.CTL TRAJ_STATE.CTL TRAJ_SCORY_SPLINE_TYPE_ENUM.CTL TRAJSECTORY_CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSFORM3D.CTL TRANSSORM3D.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	X	\( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \) \( \)	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_RC.TTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL  TRAJ_CONSTRAINT_JELIP_REGION.CTL  TRAJ_CONSTRAINT_BLLIP_REGION.CTL  TRAJ_CONSTRAINT_MAX_VELOCITY.CTL  TRAJ_CONSTRAINT_MAX_VELOCITY.CTL  TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_RECT_REGION.CTL  TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL  TRAJ_STATE.CTL  TRAJ_STATE.CTL  TRAJ_STATE.CTL  TRAJ_SCTORY_SPLINE_TYPE_ENUM.CTL  TRAJ_SCTORY_SPLINE_TYPE_ENUM.CTL  TRAJ_SCTORY_CTL  TRANSFORM3D.CTL  TRANSFORM3D.CTL  TRANSFORM3D.CTL  TRANSLATION3D.CTL  TRANSLATION3D.CTL  TRANSLATION3D.CTL  TRANSLATION3D.CTL  TRANSEZOID_PROFILE_CONSTRAINT.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	X	N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL  TIME_INTERPOLATABLE_BOOLEAN.CTL  TIME_INTERPOLATABLE_DOUBLE.CTL  TIME_INTERPOLATABLE_POSE2D.CTL  TIME_INTERPOLATABLE_ROTATION2D.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TIME_INTERPOLATABLE_VARIANT.CTL  TRAJ_CONSTG.CTL  TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL  TRAJ_CONSTRAINT_BLLIP_REGION.CTL  TRAJ_CONSTRAINT_MAX_VELOCITY.CTL  TRAJ_CONSTRAINT_MAX_VELOCITY.CTL  TRAJ_CONSTRAINT_MINMAX.CTL  TRAJ_CONSTRAINT_MINMAX.CTL  TRAJ_CONSTRAINT_MINMAX.CTL  TRAJ_CONSTRAINT_RECT_REGION.CTL  TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL  TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL  TRAJ_STATE.CTL  TRAJECTORY_SPLINE_TYPE_ENUM.CTL  TRAJECTORY_SPLINE_TYPE_ENUM.CTL  TRANSFORM2D.CTL  TRANSFORM2D.CTL  TRANSLATION2D.CTL  TRANSLATION2D.CTL  TRANSLATION2D.CTL  TRAPEZOID_PROFILE_CONSTRAINT.CTL  TRAPEZOID_PROFILE_CONSTRAINT.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z		N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL TIME_INTERPOLATABLE_BOUBLE.CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_ROTATION2D.CTL TIME_INTERPOLATABLE_ROTATION2D.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_CTL TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_BEK.CTL TRAJ_CONSTRAINT_MIN_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJ_STATE.CTL TRAJ_SCONSTRAINT_TYPE_ENUM.CTL TRAJ_SCONSTRAINT_CTL TRAJ_SCONSTRAINT_TYPE_ENUM.CTL TRAJ_SCONSTRAINT_CTL TRAJ_SCONSTRAINT_SCOT_SCONSTRAINT_CTL TRAJ_SCONSTRAINT_SCOT_SCOT_SCOT_SCOT_SCOT_SCOT_SCOT_SCO	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	X	N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL TIME_INTERPOLATABLE_DOUBLE.CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_ROTATION2D.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TRAJ_CONSTRAINT_CENTRIPETAL_ACCEL.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JELLIP_REGION.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MINMAX_CTL TRAJ_CONSTRAINT_MINMAX_CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJ_STATE.CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRAJ_STATE.CTL TRANSFORM2D.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSFORM3D.CTL TRANSFORM3D.CTL TRANSFORM3D.CTL TRANSFORM3D.CTL TRANSLATION3D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE_CTL TWIST2D.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z		N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL TIME_INTERPOLATABLE_DOUBLE_CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_ROTATION2D.CTL TIME_INTERPOLATABLE_VARIANT_CTL TIME_INTERPOLATABLE_VARIANT_CTL TIME_RCTL TRAJ_CONFIG.CTL TRAJ_CONSTRAINT_DIF_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_DIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_DIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_LIP_REGION.CTL TRAJ_CONSTRAINT_LIP_REGION.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_RECT_REGION.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRANSEORM2D.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION3D.CTL TRANSLATION3D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z		N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL TIME_INTERPOLATABLE_DOUBLE.CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_ROTATION2D.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_INTERPOLATABLE_VARIANT.CTL TIME_ROTATABLE_VARIANT.CTL TIME_CTL TRAJ_CONFIG.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_BELIP_REGION.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRANSFORM3D_CTL TRANSFORM3D_CTL TRANSFORM3D_CTL TRANSFORM3D_CTL TRANSFORM3D_CTL TRANSLATION3D_CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_CTL TWIST3D_CTL UNISCENTED_KALMAN_CORRECT_FUNC_GROUP.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z	Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z Z		N/A	SWERVE_DRIVE_POSE_EST2_INTERP_RECORD.CTL TIME_INTERPOLATABLE_BOOLEAN.CTL TIME_INTERPOLATABLE_DOUBLE_CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_POSE2D.CTL TIME_INTERPOLATABLE_ROTATION2D.CTL TIME_INTERPOLATABLE_VARIANT_CTL TIME_INTERPOLATABLE_VARIANT_CTL TIME_RCTL TRAJ_CONFIG.CTL TRAJ_CONSTRAINT_DIF_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_DIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_DIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_LIP_REGION.CTL TRAJ_CONSTRAINT_LIP_REGION.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MAX_VELOCITY.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_RECT_REGION.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRANSEORM2D.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION3D.CTL TRANSLATION3D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL	Routine exists, it is just a shell

Ζ	Z	X	Χ	N/A	UTIL_PATHFINDER_CONFIG.CTL	
N/A		N/A		N/A	WAYPOINTS.CTL	Delete – obsolete
Z	Z	X	Χ	NA	WEIGHTED_WAYPOINT.CTL	New V1.5
N/A		N/A		N/A	X_Y_HEADINGS.CTL	Delete – obsolete
Z	Z	X	Χ	N/A	X_Y_PAIR.CTL	