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...

> Doc completed Pct VI / CTL Totals 1037 950 323 979 592 51 12 91.61% VI Total (X) 929 Optimization Pct CTL Total (Z) 108
> VI Shell Total (/) 4 57.09% Optimize legend: S = Subroutine, I = Inline, X = reviewed, nothing done. (In some cases, after sufficient debug and use, additional CTRL Shell Total (\) optimizations could be considered.)

'========= BASE

'=======

ANALOG DELAY	X Implemented	\times Documented	X Not WPILIB	Menu Item	- Execution Optimized	Test Routine	Sample S VI Name AnalogDelay.vi	Function Prototype	Notes Similar to interpolated tree map	Code Review	Test Program	Error Checking
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
FUNCTION GENERATOR		Χ		X	1		FunctionGenerator_Add_Value.vi		Similar to interpolated tree map			
	Χ	Χ		X	1		FunctionGenerator_Add_XY.vi		Similar to interpolated tree map			
	Χ	Χ		X	1		FunctionGenerator_Calculate.vi		Similar to interpolated tree map			
	Χ	Χ		X	SI		FunctionGenerator_Clear.vi					
	Χ	Χ	X	Χ	1		FunctionGenerator_Execute.vi		Similar to interpolated tree map			
	Χ	Χ		X	SI		FunctionGenerator_New.vi		Similar to interpolated tree map			
FUNCTION GENERATOR MATRIX	X Implemented	X Documented	X Not WPILIB	X Menu Item	- Execution Optimized	Test Routine	ยุ่ง VI Name FunctionGeneratoMatrixr_Add.vi	Function Prototype	Notes Similar to interpolated tree map	Code Review	Test Program	Error Checking
FUNCTION GENERATOR MATRIX												
	X	X	X	X	SI		FunctionGenerator_Calculate.vi		Similar to interpolated tree map			
l	<i>X</i>	Χ	X	Ι.Χ.	51		FunctionGenerator_New.vi		Similar to interpolated tree map			

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FRC LabVIEW Trajectory Library – VI Implementat	tion List										
Revision 2.X 5/2/2022 – added implicit model follower and	l time inter שושפ שושפים שושם שושם שושפים שושים שושפים שושים	polatable Documented	PILIB	Menu Item	Test Routine	ample Program			Code Review	Test Program	Error Checking
LINEAR FIL	7	X			\	ຽ VI Name LinearFilter BackwardFiniteDifference.v	Function Prototype	Notes	<u>~~~</u>	y	<u>Ü</u>
LINEAR FIL	X			X I X SI		LinearFilter Calculate.vi					
	X	X	X	X X		LinearFilter_CutoffFrequency.vi					
	X	X	Χ	ΧI		X LinearFilter_Execute.vi		Labview style helper			
	X	X	I	Vo I		LinearFilter_Factorial.vi		AN INTERNAL ROUTINE			
	X			XX		LinearFilter_HighPass.vi					
	X	X	X	X X X X		LinearFilter_HighPassBW1.vi				-	
	X		X	$\begin{array}{c c} X & X \\ X & X \end{array}$		LinearFilter_HighPassBW2.vi LinearFilter_LowPassBW1.vi					
	X		X	X X X		LinearFilter LowPassBW2.vi					
	X			X X		LinearFilter_MovingAverage.vi					
	X	X		X I		LinearFilter_New.vi					
	X			X SI		LinearFilter_Reset.vi					
	X	X		X SI		LinearFilter_ResetToValue.vi					
	X	X		XX		LinearFilter_SinglePoleIIR.vi					
	X	X	X	XX		LinearFilter_TimeConst.vi					
	mplemented	Documented	Not WPILIB	Menu Item Execution Optim	Test Routine	Sample Progran	Function Prototype	Notes	Code Review	Test Program	Error Checking
MEDIAN FIL	TFR X			X X		MedianFilter Calculate.vi	i unction Prototype	Notes	$\overline{}$		
	X		Χ	X I		X MedianFilter Execute.vi		Labview style helper			
	X	X		X SI		MedianFilter_New.vi		1			
	X			X SI		MedianFilter_Reset.vi					
	X	X	X	X SI		MedianFilter_ResetToValue.vi					
	Implemented	Documented	Not W	Menu Item Execution Optimized	Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
SLEW RATE FIL		X		X		SlewRateLimiter_Calculate.vi					
	X			X SI		SlewRateLimiter_Close.vi					
	X	X		X I X SI		X SlewRateLimiter_Execute.vi SlewRateLimiter GetRate.vi		Labview style helper			
	X			X = SI		SlewRateLimiter_GetRate.vi					
	X			X I		SlewRateLimiter NewInitialZero.vi					
	X			X 1		SlewRateLimiter Reset.vi					
	X	X		X SI		SlewRateLimiter_SetRate.vi					
	lemented	cumented	3	Menu Item Execution Optimized	t Routine	nple Program			de Review	t Program	or Checking
	dm	900	Not	iix Me	Test	S VI Name	Function Prototype	Notes	Ö	Tes	Ξπc
TIN	MER X	-	\overline{X}	X		Timer_Close.vi	. Ended to total pe	releases semaphore		1-	4
	X	X		X		X Timer_Get.vi		·			
	X	X	X	X		Timer_GetAndReset.vi					
	L X	X	X I	VO O		Timer_GetInternal.vi		Internal (private) only	1		

FRC LabVIEW Trajectory Library - VI Implementation List Revision 2.X 5/2/2022 – added implicit model follower and time interpolatable routines.

| X | X | X | X | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X | | X Χ X Timer HasPeriodPassed.vi XXXX X Timer HasPeriodPassedOnce.vi X XX X Timer New.vi Χ XX X Timer_Reset.vi Χ X X X No Timer ResetInternal Internal (private) only XX X Timer_Start.vi Χ XX Χ X Timer_Stop.vi X X X No Timer_StopInternal.vi Internal (private) only VI Name Function Prototype Notes TIME INTERPOLATABLE BOOLEAN X Χ TimeInterpBoolean_AddSample.vi Update to use create matrix X Χ XX No TimeInterpBoolean_CleanUp.vi Update to use create matrix X X X X SI TimeInterpBoolean Clear.vi XX X TimeInterpBoolean GetSample.vi X X X X SI X X X SI TimeInterpBoolean New.vi TimeInterpBoolean SetMaxTime.vi nu Item VI Name Function Prototype Notes TIME INTERPOLATABLE DOUBLE X X TimeInterpDouble AddSample.vi X X Update to use create matrix TimeInterpDouble CleanUp.vi $X \mid X \mid X \mid No \mid I$ Update to use create matrix X X X X SI TimeInterpDouble Clear.vi X X X X I TimeInterpDouble_GetSample.vi X X X X SI TimeInterpDouble_New.vi X X X SI TimeInterpDouble_SetMaxTime.vi Item Function Prototype Notes TIME INTERPOLATABLE POSE2D X Χ Χ TimeInterpPose2d AddSample.vi X Update to use create matrix X X X No I TimeInterpPose2d CleanUp.vi Update to use create matrix X X X X SI TimeInterpPose2d Clear.vi X X X X I TimeInterpPose2d GetSample.vi X X X X SI TimeInterpPose2d New.vi TimeInterpPose2d SetMaxTime.vi $X \mid X \mid X$ SI Item Function Prototype TIME INTERPOLATABLE ROTATION2D X X TimeInterpRotation2d AddSample.vi X X Update to use create matrix X X X No I TimeInterpRotation2d CleanUp.vi

X X X X SI

X X X X I

X X X X SI

X X X SI

TimeInterpRotation2d Clear.vi

TimeInterpRotation2d New.vi

TimeInterpRotation2d_GetSample.vi

TimeInterpRotation2d SetMaxTime.vi

Update to use create matrix

ded implicit model follower and tin	ie iritei	polata	bie rot	unes.								
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
DIGITAL SEQUENTIAL LOGIC							DigSeqLogic_Delay.vi					
	X	X	X	Χ			DigSeqLogic_On_Delay.vi					
	X		X	Χ			DigSeqLogic_Off_Delay.vi					
	X	X	X	X			DigSeqLogic_One_Shot.vi					
	X	X	Χ	Χ			DigSeqLogic_SR_Flip_Flop.vi					
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
DEBOUNCE				Χ			Debouncer_New.vi					
	X	X		Χ			Debouncer_Calculate.vi					
	X	X	X	Χ			Debouncer_Execute.vi					
	X	X		No			Debouncer_Reset.vi					
	X	X		No			Debouncer_HasElapsed.vi					

'========= CONTROLLER '========

> VI Name Function Prototype Notes ARM FF X X X X X X X X ArmFF Calculate.vi ArmFF CalculateVelocityOnly.vi Χ X ArmFF_Execute.vi LabVIEW style single call LabVIEW style single call ArmFF_ExecuteVelocityOnly.vi
> ArmFF_MaxAchieveAccel.vi X X XX Χ ArmFF_MaxAchieveVelocity.vi XX Χ ArmFF_MinAchieveAccel.vi ArmFF_MinAchieveVelocity.vi ArmFF_New_ZeroGravity.vi XX Χ XX Χ ArmFF_New.vi XX X

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
BANG BANG	X	X		X	SI		BangBang_AtSetpoint.vi					
	Χ	X		X	SI		BangBang_Calculate_PV.vi					
	Χ	X		X	SI		BangBang_Calculate_SP_PV.vi					
	Χ	X	X	X	SI		BangBang_Execute.vi					
	Χ	X		Χ	SI		BangBang_GetAll.vi					
	X	X		X	SI		BangBang_GetError.vi					

y – VI Implementation Lis	st											
cit model follower and time in	terpola	table r					D D N					
)	Υ .	<u> </u>	+ ?	(5	51		BangBang_New.vi					
/	Χ . Χ .	Υ	,	(5	SI SI		BangBang_SetSetpoint.vi BangBang_SetTolerance.vi					
	^ .	\		(3)		Bangbang_Set i olerance.vi					
CONTROLLER UTIL		Not WPILIB			ב ע		VI Name	Function Prototype	Notes This was short lived in WOULD, but	Code Review	Test Program	Error Checking
CONTROLLER UTIL	X .	<)	(5	61		ControllerUtil_GetModulusError.vi		This was short lived in WPILIB, but still useful here.			
ELEV FF		Not WPILIB			Execution Optimized	Test Routine	VI Name ElevFF Calculate.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
		<u>`</u>					ElevFF_CalculateVelocityOnly.vi					
		X					ElevFF_Execute.vi		LabVIEW style single call			
		X					ElevFF ExecuteVelocityOnly.vi		LabVIEW style single call			
		((ElevFF_MaxAchieveAccel.vi					
		(,				ElevFF_MaxAchieveVelocity.vi					
		(,				ElevFF_MinAchieveAccel.vi					
		Υ	,				ElevFF_MinAchieveVelocity.vi					
		Υ	,	(ElevFF_New_ZeroAccel.vi ElevFF_New.vi					
	nemented	Not WPILIB	77		Execution Opt	Test Routine	NI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
HOL_DRV_CTRL				<u>≥ u</u>	u		HolDrvCtrl AdvCalculate Trajectory.vi	Function Frototype	Added 1/24/2022	0	7	
1102_51(12_5	X	$\frac{1}{X}$	· ')	<u>`</u>			HolDrvCtrl_AdvCalculate.vi		Added 1/24/2022			
	x .	<i>Χ Χ</i>	7	< s	S/		HolDrvCtrl_AtReference.vi		Added 1/26/21			
	X .	((l l		HolDrvCtrl_Calculate_Trajectory.vi		Added 1/26/21			
		((1		HolDrvCtrl_Calculate.vi		Added 1/26/21			
	X .	(X	,				HolDrvCtrl_Execute_Trajectory.vi		Added 1/24/2022			
		Υ X					HolDryCtrl_Execute.vi		Future Added 1/26/21			
		(SI SI		HolDrvCtrl_New.vi HolDrvCtrl_PackExecuteSP.vi		Added 1/20/21			
		$\begin{array}{c c} X & X \\ \hline X & X \end{array}$			-		HolDrvCtrl_PackPID.vi		Added 1/24/2022			
	X Z						HolDrvCtrl PackProfPID.vi		Added 1/24/2022			
	Υ .	((5	31		HolDrvCtrl_SetEnabled.vi		Added 1/26/21			
	Υ .	<	7	(5	8/		HolDrvCtrl_SetTolerance.vi		Added 1/26/21			
	X .	Κ)	(5	SI DAY							
		Documented Not WPILIB				Test Routine	NI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
PID CONTROLLER							PIDController_AdvCalculate_FF_Sp_Pv_Per.vi	<u>, , , , , , , , , , , , , , , , , , , </u>	Advanced PID			
1 12 0011111022211 7												
	Υ .	<i>(X</i>	· ;	(PIDController_AdvCalculate_FF_Sp_Pv.vi		Advanced PID			
	Υ .		· ;	(PIDController_AdvCalculate_FF_Sp_Pv.vi PIDController_AdvExecute.vi					

e interp	olatab	le rou	ıtines.			
X	X		Χ	SI	PIDController_AtSetpoint.vi	
X	X		Χ		PIDController_Calculate_PV.vi	
X	X		Χ		PIDController_Calculate_SP_PV.vi	
X	X		Χ	SI	PIDController_DisableContinousInput.vi	
X	X		Χ	SI	PIDController_EnableContinousInput.vi	
X	X	Χ	Χ		X PIDController_Execute.vi	Labview style helper
					PIDController_GetContinuousError.vi	OBSOLETE – Removed
X	X		Χ	SI	PIDController_GetPeriod.vi	
X	X		Χ	SI	PIDController_GetPID.vi	
X	X		Χ	SI	PIDController_GetPositionError.vi	
X	X		Χ	SI	PIDController_GetSetpoint.vi	
X	X		Χ	SI	PIDController_GetVelocityError.vi	
X	X		Χ	SI	PIDController_IsContinuousInputEnabled.vi	
X	X		Χ	1	PIDController_New.vi	
X	X		Χ	1	PIDController_NewPeriod.vi	
X	X	Χ	Χ	SI	PIDController Pack AdvLimits.vi	
X	X	Χ	Χ	SI	PIDController Pack AdvTuning.vi	
X	X	Χ	Χ	SI	PIDController Pack ErrorTolerance.vi	
X	X	Χ	Χ	SI	PIDController Pack InputLimits.vi	
X	X	Χ	Χ	SI	PIDController_Pack_Tuning.vi	
X	Χ		Χ	SI	PIDController_Reset.vi	
X	X		Χ	SI	PIDController SetD.vi	
X	Χ	Χ	Χ	SI	PIDController_SetDerivativeFilter.vi	Advanced PID
X	X	Χ	No		PIDController_SetFeedForward_OBSOLETE_DELETE.vi	Advanced PID, Obsolete –
						DELETE
X	X	X	No		PIDController_SetFFGain_OBSOLETE_DELETE.vi	Advanced PID, Obsolete –
. V	. V		V/	01	DIPO antarilar Catlari	DELETE
X	Χ		Χ	SI	PIDController_SetI.vi PIDController_SetInputRange.vi	OBSOLETE – Removed
V	Х		X	SI	PIDController_SetIntegratorRange.vi	OBSOLETE – Removed
X	X	X	X	SI	PIDController_SetUntegratorRange.vi	Advanced PID
					PIDController_SetOutputElmits.vi	Advanced PID
X	X	V	X	SI	PIDController_SetP.vi PIDController SetPeriod.vi	
X	X	Χ	X	SI SI	PIDController_SetPID.vi	
		V		SI		Advanced DID
X	X	X	X		PIDController_SetPIDF.vi	Advanced PID
X	X		X	SI	PIDController_SetSetpoint.vi	
X	X		X	SI	PIDController_SetTolerance.vi	
X	X		X	SI	PIDController_SetTolerancePandV.vi	

Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
PROFILED PID CONTROLLER X	X		X	SI			ProfiledPIDController_AtGoal.vi					
X	X		X	SI			ProfiledPIDController_AtSetpoint.vi					
X	X		X				ProfiledPIDController_Calculate_Meas_Goal.vi					
X	X		X				ProfiledPIDController_Calculate_Meas_StateGoal_TrapCnsrt.vi					
X	X		Χ				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	X	X	X	I			ProfiledPIDController_Execute.vi		Single call LabVIEW style function.			
X	X		Χ	SI			ProfiledPIDController GetGoal.vi					
X	X		Χ	SI			ProfiledPIDController GetPeriod.vi					
X	X	X	Χ	SI			ProfiledPIDController GetPID.vi		WPILIB has separate getters.			
X	X		Χ	SI			ProfiledPIDController GetPositionError.vi		·			
X	X		Χ	SI			ProfiledPIDController GetSetpoint.vi					
X	X		Χ	SI			ProfiledPIDController_GetVelocityError.vi					
X	X		Χ	1			ProfiledPIDController New.vi					
X	X		X	1			ProfiledPIDController NewPeriod.vi					
X	X		Х	SI			ProfiledPIDController Reset PosOnly.vi					

EDC LabVIEW Traington/Library VI Implementation	Liet										
FRC LabVIEW Trajectory Library – VI Implementation Revision 2.X 5/2/2022 – added implicit model follower and tim		latahl	e routii	168			<u> </u>				
Revision 2.X 3/2/2022 – added implicit model follower and tim		X		X S	1	ProfiledPIDController Reset PosVel.vi					
		X		X		ProfiledPIDController Reset.vi					
	X	X		X		ProfiledPIDController SetConstraints.vi					
		X		X		ProfiledPIDController_SetGoal_PosOnly.vi					
		X		X S		ProfiledPIDController SetGoal.vi					
		X		X S		ProfiledPIDController_SetIntegratorRange.vi					
		X		X S	1	ProfiledPIDController_SetPID.vi					
	X			$X \mid S$		ProfiledPIDController_SetTolerance_PosOnly.vi					
	X	X		$X \mid S$	1	ProfiledPIDController_SetTolerance_PosVel.vi					
	Implemented	Documented	Not N	Menu Item			Function Prototype	Notes	Code Review	Test Program	Error Checking
RAMSETE				X S		Ramsete_AtReference.vi	AtReference				
		Χ		X		Ramsete_Calculate_Trajectory.vi	calculate_trajectory				
	X			X		Ramsete_Calculate.vi	calculate				
	X	X	X	X		Ramsete_Diff_DO_Eng.vi					
	X	X	X X	X X		Ramsete Diff_DO_SI.vi Ramsete Execute ENG.vi	Use this one!!				
	X	X		X S		Ramsete_Execute_End.vi Ramsete_Execute_PackTuning_ENG.vi	Ose triis one!!				
				X S		Ramsete_Execute_PackTuning_ENG.vi					
	X	X	X	X		Ramsete Execute.vi					
	X	X		X		Ramsete New B Z.vi	new(b, zeta)				
		X		X		Ramsete New.vi	new				
	X	X		X S		Ramsete SetEnabled.vi	SetEnabled				
	X	X		X S	1	Ramsete_SetTolerance.vi	SetTolerance				
	X	Χ		X		Ramsete_SINC.vi	sinc	internal			
				7	3						
SIMPLE MOTOR FEEDFORWARD	$\begin{array}{c c} X \\ X \end{array}$	X	X	X S	Test Routil	SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
SIMPLE MOTOR FEEDFORWARD	X X X	X X X	X	X X Menu Item		SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi SimpleMotorFF_Calculate.vi	public double calculate(double velocity, double acceleration)	Notes	Code Review	Test Program	Error Checking
SIMPLE MOTOR FEEDFORWARD	X X X	X	X	X X Menu Item		SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi	public double calculate(double velocity, double acceleration) public double calculate(double velocity) public double maxAchievableAcceleration(double maxVoltage,	Notes	Code Review	Test Program	Error Checking
SIMPLE MOTOR FEEDFORWARD	X X X X	X X X	X	X Wenu Item X X X X X X X X X X X X X X X X X X X		SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi SimpleMotorFF_Calculate.vi SimpleMotorFF_CalculateVelocityOnly.vi SimpleMotorFF_MaxAchieveAccel.vi SimpleMotorFF_MaxAchieveVel.vi	public double calculate(double velocity, double acceleration) public double calculate(double velocity) public double maxAchievableAcceleration(double maxVoltage, double velocity) public double maxAchievableVelocity(double maxVoltage, double acceleration)		Code Review	Test Program	Error Checking
SIMPLE MOTOR FEEDFORWARD	X X X X X X X X X	X X X X X X	X	X X X X X X X X X X X X X X X X X X X		SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi SimpleMotorFF_Calculate.vi SimpleMotorFF_CalculateVelocityOnly.vi SimpleMotorFF_MaxAchieveAccel.vi SimpleMotorFF_MaxAchieveVel.vi SimpleMotorFF_MinAchieveAccel.vi	public double calculate(double velocity, double acceleration) public double calculate(double velocity) public double maxAchievableAcceleration(double maxVoltage, double velocity) public double maxAchievableVelocity(double maxVoltage, double acceleration) public double minAchievableAcceleration(double maxVoltage, double velocity)		Code Review	Test Program	Error Checking
SIMPLE MOTOR FEEDFORWARD	X X X X X X X X X X X X X X X X X X X	X X X X X X	X	X X X X X X X X X X X X X X X X X X X		SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi SimpleMotorFF_Calculate.vi SimpleMotorFF_CalculateVelocityOnly.vi SimpleMotorFF_MaxAchieveAccel.vi SimpleMotorFF_MaxAchieveVel.vi SimpleMotorFF_MinAchieveAccel.vi	public double calculate(double velocity, double acceleration) public double calculate(double velocity) public double maxAchievableAcceleration(double maxVoltage, double velocity) public double maxAchievableVelocity(double maxVoltage, double acceleration) public double minAchievableAcceleration(double maxVoltage, double velocity) public double minAchievableVelocity(double maxVoltage, double acceleration)		Code Review	Test Program	Error Checking
SIMPLE MOTOR FEEDFORWARD	X X X X X X X X X	X X X X X X	X	X X X X X X X X X X X X X X X X X X X		SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi SimpleMotorFF_Calculate.vi SimpleMotorFF_CalculateVelocityOnly.vi SimpleMotorFF_MaxAchieveAccel.vi SimpleMotorFF_MaxAchieveVel.vi SimpleMotorFF_MinAchieveAccel.vi	public double calculate(double velocity, double acceleration) public double calculate(double velocity) public double maxAchievableAcceleration(double maxVoltage, double velocity) public double maxAchievableVelocity(double maxVoltage, double acceleration) public double minAchievableAcceleration(double maxVoltage, double velocity) public double minAchievableVelocity(double maxVoltage, double acceleration) public SimpleMotorFeedforward(double ks, double kv, double ka)		Code Review	Test Program	Error Checking
SIMPLE MOTOR FEEDFORWARD	X X X X X X X X X X X X X X X X X X X	X X X X X X	X	X X X X X X X X X X X X X X X X X X X		SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi SimpleMotorFF_Calculate.vi SimpleMotorFF_CalculateVelocityOnly.vi SimpleMotorFF_MaxAchieveAccel.vi SimpleMotorFF_MaxAchieveVel.vi SimpleMotorFF_MinAchieveAccel.vi	public double calculate(double velocity, double acceleration) public double calculate(double velocity) public double maxAchievableAcceleration(double maxVoltage, double velocity) public double maxAchievableVelocity(double maxVoltage, double acceleration) public double minAchievableAcceleration(double maxVoltage, double velocity) public double minAchievableVelocity(double maxVoltage, double acceleration)		Code Review	Test Program	Error Checking
SIMPLE MOTOR FEEDFORWARD '===================================	X X X X X X X X X X X X X X X X X X X	X X X X X X X X	X	X X X X X X X X X X X X X X X X X X X		SimpleMotorFF_Calculate_CalcAccel.vi SimpleMotorFF_Calculate_NextV_Dt.vi SimpleMotorFF_Calculate.vi SimpleMotorFF_CalculateVelocityOnly.vi SimpleMotorFF_MaxAchieveAccel.vi SimpleMotorFF_MaxAchieveVel.vi SimpleMotorFF_MinAchieveAccel.vi SimpleMotorFF_MinAchieveVel.vi SimpleMotorFF_MinAchieveVel.vi	public double calculate(double velocity, double acceleration) public double calculate(double velocity) public double maxAchievableAcceleration(double maxVoltage, double velocity) public double maxAchievableVelocity(double maxVoltage, double acceleration) public double minAchievableAcceleration(double maxVoltage, double velocity) public double minAchievableVelocity(double maxVoltage, double acceleration) public SimpleMotorFeedforward(double ks, double kv, double ka)		Code Review	Test Program	Error Checking

implicit model follower and ti		polatal	ole rout	ines.					-				
COORDINATE AX				Χ	SI			CoordAxis_D.vi					
	X			Χ	SI SI			CoordAxis_E.vi					
	X	X		Χ	SI			CoordAxis_N.vi					
	X	X		Χ				CoordAxis New.vi					
	X	X		Χ	SI			CoordAxis_S.vi					
	X	X		Χ	SI			CoordAxis_U.vi					
	X	X		Χ	SI			CoordAxis_W.vi					
												<u> </u>	
COORDINATE SYSTEM	X	X	Not WPILIB	X X Menu Item	ଓ ଓ ଓ Execution Optimized	X Test Routine		VI Name CoordSystem_Convert_Pose3d.vi CoordSystem_Convert_Rotation3d.vi CoordSystem_Convert_Translation3d.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
	X	X		Χ	SI	X		CoordSystem_EDN.vi					
	X	X		Χ	SI	X		CoordSystem_NED.vi					
	X	Χ		Χ	SI	X		CoordSystem_New.vi					
	X	X		Χ	SI	Χ		CoordSystem_NWU.vi					
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program				Code Review	st Program	or Checking
	m	ŏ	Ş	Me	Ϋ́	ĕ	Sai	VI Name	Function Prototype	Notes	Š	Test	Error
POSE2I		X		\overline{X}	SI		٠,	Pose2d_Equals.VI	boolean equals(other obj)				7
	X	X		X	X			Pose2d_Exp.vi	pose2d exp(twist2d twist)				
	X	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	X	SI			Pose2d_getXY.vi	a anotation 20 gott ramolation ()	san also uso claste, ampaex			
	X	X	X	X	SI			Pose2d_getXYAngle.vi					
	X	X		X	1			Pose2d Interpolate.vi					
	X	X		X	Χ			Pose2d_Log.vi	twist2d log(pose2d end)				
	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		X	SI			Pose2d New.vi	pose2d new(double x, double y, rotation2d)				
	X	X		X				Pose2d_Plus.vi	pose2d plus(transform2d other)				
	X	X		Χ	SI SI			Pose2d RelativeTo.vi	pose2d relativeto(pose2d other)				
	X	X		Χ	SI			Pose2d_TransformBy.vi	pose2d transformby(transform2d other)				
									pose2d new()	can use cluster constant			
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program				Code Review	st Program	Error Checking
			_ ≥				S	VI Name	Function Prototype	Notes			Er
POSE3I				Χ	SI			Pose3d_Equals.VI					
	X	X		Χ	X SI			Pose3d_Exp.vi					
	X	X		Χ	SI			Pose3d_getRotation.vi					
	X	X		Χ	SI			Pose3d_getTranslation.vi					
	X	X	X	Χ	SI			Pose3d_getXYZ.vi					
	X	X		Χ	1			Pose3d_Interpolate.vi					
	X	X		Χ	Χ			Pose3d_Log.vi					
	X	X		Χ	SI			Pose3d_Minus.vi					
	X	X		Χ	SI			Pose3d_New.vi					
	X	X		X	SI			Pose3d_New_Default.vi					
	X	X		Χ	SI			Pose3d_New_Trans3dRot3d.vi					

FRC LabVIEW Trajectory Library – VI Implementation List

Revision 2.X 5/2/2022 – added implicit model follower and time interpolatable routines.

| X | X | | X | SI | | | Pose3d_Plus.vi

ŗ	X	Χ		Χ	SI			Pose3d_Plus.vi					
ļ	Χ				SI			Pose3d_RelativeTo.vi					
	Χ	Χ		No	SI			Pose3d_RotationVectorToMatrix.vi					
		Χ		Χ	SI			Pose3d_ToPose2d.vi					
	X	Χ		Χ	SI			Pose3d_TransformBy.vi					
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
QUATERNION	X			X	SI			Quaternion_Equals.vi					
	X			X	SI			Quaternion_Get_All.vi					
	X			X				Quaternion_Get_LVQuat.vi					
	X			X	SI			Quaternion_Get_Vect.vi					
	X			X	SI SI			Quaternion_Get_W.vi Quaternion Inverse.vi					
	X	V			SI			Quaternion_inverse.vi Quaternion New.vi					
	X	\hat{x}		X	SI			Quaternion New Default.vi					
	X			X				Quaternion New LVQuat.vi					
	X			X	SI			Quaternion Normalize.vi					
ŀ	X			X	SI			Quaternion Plus.vi					
ŀ	Χ			Χ	SI			Quaternion Times.vi					
1	Χ				SI			Quaternion_ToRotationVector.vi					
	Implemented	Documentec	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Revie	Test Program	Error Checking
ROTATION2D	Χ	Χ		Χ	SI			Rotation2d_CreateAngle.vi	rotation2d new(double value)				
	Χ			Χ	SI			Rotation2d_CreateAngleDegrees.vi	rotation2d fromDegrees(double degrees)	convert to radians then create			
	X	X		X	SI			Rotation2d_CreateAngleRotations.vi					
	X			<u> X</u>	SI			Rotation2d_CreateXY.vi	rotation2d new(double x, double y)				
	X	X		X	SI			Rotation2d_Equals.vi Rotation2d GetAngleCosSin.vi	boolean equals(rotation2d other)	New 1/26/21			
	X Y	X V		X	SI			Rotation2d_GetCos.VI	double getCos()	use cluster unpack			
	X	X		X	SI			Rotation2d_GetDegrees.VI	double getDegrees()	use cluster unpack, then convert to degree			
ļ	Χ	X		X	SI			Rotation2d_GetRadians.VI	double getRadians()	use cluster unpack			
	X	X		X	SI			Rotation2d_GetRotations.vi	1.11.00.0				
	X	X		X	SI			Rotation2d_GetSin.VI	double getSin()	use cluster unpack			
	X	X		X	SI SI			Rotation2d_GetTan.VI Rotation2d_Interpolate.vi	double getTan()	can calculate			
	X				SI			Rotation2d_Interpolate.vi	rotation2d minus(rotation2d other)				
	X			X	SI			Rotation2d_Plus.vi	rotation2d rotation2d other)				
ŀ	X			X	SI			Rotation2d_RotateBy.vi	rotation2d rotateby(rotation2d other)				
ŀ	Χ				SI			Rotation2d Times.vi	rotation2d times(double scalar)				
	Χ	X		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				Code Review	Test Program	Checking

FRC LabVIEW Trajectory Library – VI Implementation List Revision 2.X 5/2/2022 – added implicit model follower and time inter ROTATION3D X

vi implementation													
nodel follower and time ROTATION3D		polatar	ie rou		SI	Ι		Datation2d Croate AvisAngla vi					
ROTATIONSD	X			X	SI			Rotation3d_Create_AxisAngle.vi Rotation3d Create Default.vi					
				X	SI			Rotation3d_Create_Default.vi Rotation3d Create Quaternion.vi					
	X			X	SI			Rotation3d_Create_Quaternion.vi Rotation3d_Create_RollPitchYaw.vi					
	X				SI			Rotation3d_Create_RollPlicf1Yaw.vl Rotation3d_Equals.vi					
	X			X	SI								
			Χ	X V	SI			Rotation3d_GetAxisAngle.vi					
	X			X	SI			Rotation3d_GetQuaternion.vi					
	X			X	SI			Rotation3d_GetXYZ.vi					
	X			X				Rotation3d_Interpolate.vi					
	X			X	SI			Rotation3d_Minus.vi					
	X			X	SI			Rotation3d_Plus.vi					
	X			X	SI			Rotation3d_RotateBy.vi					
	X			X	SI			Rotation3d_Times.vi					
	X			X	-01			Rotation3d_ToRotation2d.vi					
	X			Χ	SI			Rotation3d_UnaryMinus.vi					
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	le Program				Code Review	rogram	Error Checking
	len	'n	3	ת	in cr	#: X	Sample				- Je	έ. σ	9, 0
	du	90	Q	Je.	:: G	ခ်	San	VI Name	Function Prototype	Notes	8	Test	2LL
TRANSFORM2D		X	_<_	X	SI			Transform2d Create PosePose.vi	transform2d new(pose2d, pose2d)	Notes			
I KANSFURIVIZU				Λ V	SI								
	X	X		X	SI SI			Transform2d_Create_TransRot.vi	transform2d new(translation2d, rotation2d)				
	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		Χ	Χ	SI			Transform2d_GetXY.vi					
	X		Χ	Χ	SI			Transform2d_GetXYAngle.vi					
		X		Χ	SI			Transform2d_Inverse.vi	transform inverse()	new			
	Χ	X		Χ	Si			Transform2d_Plus.vi					
	X	X		Χ	SI			Transform2d_Times.vi	transform2d times(double scalar)				
									transform2d new()	can use cluster constant			
TRANSFORM3D	X X X Implemented	Documented	Not WPILIB	X X Menu Item	인 연 의 Execution Optimized	Test Routine	Sample Program	VI Name Transform3d_Create_Default.vi Transform3d_Create_Pose3dPose.3dvi Transform3d_Create_Trans3dRot3d.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
	X			Χ	SI			Transform3d_Equals.VI					
	Χ			Χ	SI			Transform3d_GetRotation3d.VI					
	X			Χ	SI			Transform3d_GetTranslation3d.VI					
	Χ		Χ	Χ	SI			Transform3d_GetXYZ.vi					
	X			Χ	SI			Transform3d_Inverse.vi					
	X			Χ	Si			Transform3d_Plus.vi					
	X			Χ	SI			Transform3d_Times.vi					
	Implemented	Documented	Not WPILIB	nu Item	Execution Optimized	Test Routine	Sample Program				Code Review	t Program	or Checking
	ηD	900	lot	Menu	×e	ės.	an	VI Name	Function Prototype	Notes	ò	es.	Error
TRANSLATION2D		P	_ Z	≥ ∨			S	Translation2d_Create_DistAng.vi	т инолон гтологуре	INOTES	U	7	Ш
I RANGLA HUNZD				X	SI SI	1		Translation2d_Create_DistAng.vi Translation2d Create.vi	translation2d naw(dauble x, dauble x)				
	X	, X		٨	ા		1	Translau0HZU_Create.vi	translation2d new(double x, double y)				

nodel follower and time			le rout										
	X			Χ	SI			Translation2d_Equals.vi	boolean equals(translation other)				
	X	X		Χ	SI			Translation2d_GetAngle.vi					
	Χ	X		Χ	SI			Translation2d GetDistance.vi	double getDistance(translation2d other)				
	X	X		X	SI			Translation2d_GetNorm.VI	double getNorm()	can use cluster unpack			
	X	X		X	SI			Translation2d GetX.VI	double getX()	can use cluster unpack			
	X	X	Χ	X	SI			Translation2d GetXY.VI	double get/()	can use cluster unpack			
			^	^	01				-lk-l				
	X	X		Χ	SI			Translation2d_GetY.VI	double getY()	can use cluster unpack			
	X	X		Χ	SI			Translation2d_Interpolate.vi					
	X	X		Χ	SI			Translation2d_Minus.vi	translation2d minus(translation2d other)				
	X	X		Χ	SI			Translation2d_Plus.vi	translation2d plus(translation2d other)				
	X	X		X	SI			Translation2d_RotateBy.vi	translation2d rotateBy(rotation2d other)				
	X	X		Χ	SI			Translation2d Times.vi	translation2d times(double scalar)				
	X	X		X	SI			Translation2d_UnaryMinus.vi	translation2d unaryminus()				
	7.	,,		,,	<u> </u>			Translation 22_Orial Junitarium	translation2d new()	can use cluster constant			
									translation2d div(double scalar)	can multiply by 1/scalar			
									translation2d div(double scalar)	can multiply by 1/scalar			
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
TRANSLATION3D	X			\overline{X}	SI			Translation3d_Create.vi	- Carrottering per				
ITANOLATIONOD	X			X	SI			Translation3d Create Default.vi					
	X			X	SI					+			
					31			Translation3d_Create_DistAng.vi					
	X			Χ	SI			Translation3d_Div.vi					
	Χ			Χ	SI			Translation3d_Equals.vi					
	X			Χ	SI			Translation3d_GetDistance.vi					
	X			X	SI			Translation3d GetNorm.VI					
	X		Χ	X	SI			Translation3d_GetXYZ.vi					
	X			X	SI			Translation3d_Interpolate.vi					
					SI			Translation3d_Interpolate.vi					
	X			X									
	X			Χ	SI			Translation3d_Plus.vi					
	Χ			Χ	SI			Translation3d_RotateBy.vi					
	X			Χ	SI			Translation3d_Times.vi					
	X			Χ	SI			Translation3d ToTranslation2d.vi					
	X			Χ	SI			Translation3d UnaryMinus.vi					
TWIST2D	Implemente	X X Documented	X Not WPILIB	X X Menu Item	일 열 Execution Optimized	Test Routine		VI Name Twist2d_Create.vi Twist2d_Equals.VI Twist2d_GetAll.VI	Function Prototype twist new(x, y, theta) boolean equals(obj other)	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
TWIST3D	X			\overline{X}	SI	X		Twist3d_Create.vi					_
	X			X	SI	X		Twist3d Equals.VI					
	X		Χ	X	SI			Twist3d_GetAll.VI					
			^	^	- 51			1 1110.00 a_ 000 til. V l					

'========= KINEMATICS '========

022 – added implicit model follower and time	interpo	olatab	le rou	tines					-				
ozz addod impiloti modor followor dna timo	, into p	olutub	10 100		þ								
CHASSIS SPEEDS		X X Documented	X Not WPILIB	X Menu Item	ର ଓ Execution Optimize	Test Routine		VI Name ChassisSpeeds_FromFieldRelativeSpeeds.VI ChassisSPeeds_GetXYOmega.vi ChassisSpeeds_New.vi	chassisspeeds fromFieldRelativeSpeeds(double x, double y, double angvel, rotation2d robotangle) chassisspeeds new (double xvel, double yvel, double angvel)	Notes can use cluster constant	Code Review	Test Program	Error Checking
									·	-			
DIFFERENTIAL DRIVE KINEMATICS		X Documented	Not WPILIB	X Menu Item	- Execution Optimized	X Test Routine		VI Name DiffKinematics_New.vi	diffDriveKine new(double trackWidth)	Notes	Code Review	Test Program	Error Checking
	X	Χ		Χ	Χ	Χ		DiffKinematics_toChassisSpeed.vi	chassisSpeeds toChassisSpeeds(diffDrWheelSpeeds)				
	X	X		Χ	SI	X		DiffKinematics_toWheelSpeed.vi	diffDriveWheelSpeed toWheelSpeeds(chassisSpeeds)				
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine		VI Name		Notes	Code Review	Test Program	Error Checking
DIFFERENTIAL DRIVE ODOMETRY			Χ					DiffOdometry_Execute.vi		DONT NEED			
	X	X		X	X			DiffOdometry_Update.vi	pose2d update(rotation2d gyro, double leftdist, double right dist) diffDrOdom new(rotation gyro, pose initial) diffDrOdom new(rotation gyro) void resetPosition(pose2d, rotation2d) pose2d getPoseMeters()	Incorporates enhanced reset incorporated into "update"			
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name		Notes	Code Review	Test Program	Error Checking
DIFFERENTIAL DRIVE WHEEL SPEEDS									diffDrWheelSpeeds new()				
	V	V		V	V			DiffM/bool Normaliza vi	diffDrWheelSpeeds new(double leftVel, double rightVel)				
l	Χ	X		Χ	X			DiffWheel_Normalize.vi	void normalize(double maxVel)				
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program				Code Review	sst Program	Error Checking
_			≥		Щ				Function Prototype	Notes	გ	7e	Щ
MECANUM DRIVE KINEMATICS		Χ		Χ	I			MecaKinematics_New.vi					
	Χ	Χ		Χ	Χ			MecaKinematics_SetInverseKinematics.vi					
	Χ	Χ		Χ	Χ			MecaKinematics_ToChassisSpeeds.vi					
	Χ	Χ		Χ	Χ			MecaKinematics_ToWheelSpeeds.vi					
l	X	Χ		Χ	Χ			MecaKinematics_ToWheelSpeedsZeroCenter.vi					

array and "4" calls)

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	ଞ୍ଚ VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
SWERVE DRIVE ODOMETRY							SwerveOdometry_Execute4.vi					
							SwerveOdometry_ExecuteX.vi					
	Χ			X			SwerveOdometry_GetPosition.VI	public Pose2d getPoseMeters()				
	X	X		X			SwerveOdometry_New.VI	public SwerveDriveOdometry(SwerveDriveKinematics kinematics, Rotation2d gyroAngle, Pose2d initialPose)				<u> </u>
	X	X		X			SwerveOdometry_NewZeroCenter.VI	public SwerveDriveOdometry(SwerveDriveKinematics kinematics, Rotation2d gyroAngle)				
	X			X			SwerveOdometry_ResetPosition.VI	public void resetPosition(Pose2d pose, Rotation2d gyroAngle)				
	Χ	X	X	X			SwerveOdometry_Update4.VI		For 4 module drives			
	X	X	X	X			SwerveOdometry_UpdateWithTime4.VI		For 4 module drives			
	Χ		X	X			SwerveOdometry_UpdateWithTimeX.VI		uses array as input			
	X	X	X	X			SwerveOdometry UpdateX.VI		uses array as input			
								public Pose2d updateWithTime(double currentTimeSeconds, Rotation2d gyroAngle, SwerveModuleState moduleStates)	variable parameters (replace with array and "4" calls)			
								public Pose2d update(Rotation2d gyroAngle, SwerveModuleState moduleStates)	variable parameters (replace with array and "4" calls)			
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine		Function Prototype	Notes	Code Review	Test Program	Error Checking
SWERVE DRIVE MODULE STATE	X	X		X	SI		SwerveModuleState_CompareTo.vi	public int compareTo(SwerveModuleState o)				
				X	SI		SwerveModuleState_Get.vi					
	Χ	X		X	SI		SwerveModuleState_New.vi	public SwerveModuleState(double speedMetersPerSecond, Rotation2d angle)				
	X	X		X	SI		SwerveModuleState_Optimize.vi	public SwerveModuleState optimize(SwerveModuleState desired, Rotation2d angle)	,			<u> </u>

'====== SPLINE '=======														
		Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
	CUBIC HERMITE SPLINE								`	protected SimpleMatrix getCoefficients()	not needed, use cluster unpack			
		X	X		X				CubicHermiteSpline_getControlVectorFromArrays.vi	private SimpleMatrix getControlVectorFromArrays(double[] initialVector, double[] finalVector)				
		X	Χ		Χ				CubicHermiteSpline_makeHermiteBasis.vi	private SimpleMatrix makeHermiteBasis()				
		X	X		X				CubicHermiteSpline_New.vi	public CubicHermiteSpline(double[] xInitialControlVector, double[] xFinalControlVector, double[] yInitialControlVector, double[] yFinalControlVector)				

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program ≤	Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
POSE WITH CURVATURE	X	X		Χ	SI		Po	oseWithCurve_New.vi	public PoseWithCurvature(Pose2d poseMeters, double				
									curvatureRadPerMeter)				
									public PoseWithCurvature()	can use cluster constant			

ed implicit model follower and time		oolatal	ble roi	utines									
I I I I I I I I I I I I I I I I I I I		2.3(3)							public Pose2d poseMeters	not needed, use cluster unpack			
									public double curvatureRadPerMeter	not needed, use cluster unpack			
					75								
QUINTIC HERMITE SPLINE	X X X X X X X X X X	X Documented	Not WPILIB	X X Menu Item	Execution Optimized	Test Routine		VI Name QuinticHermiteSpline_getControlVectorFromArrays.vi QuinticHermiteSpline_makeHermiteBasis.vi QuinticHermiteSpline_New.vi	Function Prototype private SimpleMatrix getControlVectorFromArrays(double[] initialVector, double[] finalVector) private SimpleMatrix makeHermiteBasis() public QuinticHermiteSpline(double[] xInitialControlVector, double[] xFinalControlVector, double[] yInitialControlVector,	Notes	Code Review	Test Program	Error Checking
									double[] vFinalControlVector)				
									protected SimpleMatrix getCoefficients()	not needed, use cluster unpack			
	(Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine		VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
SPLINE (Abstract class)	Χ	Χ		X				Spline_getPoint.vi	public PoseWithCurvature getPoint(double t)				
									Spline(int degree)				
									public static class ControlVector public ControlVector(double[] x, double[] y)	implemented as data structure			
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optim	Test Routine	Sample Program		5. (° B.)		Code Review	est Program	Error Checking
SPLINE HELPER			_ <					VI Name	Function Prototype private static Spline.ControlVector getCubicControlVector(double	Notes	O	, i	Щ
SPLINE HELPER	X	X		X	SI			SplineHelp_GetCubicCtrlVector.vi	scalar, Pose2d point)				
	X	X		X		X		SplineHelp_GetCubicCtrlVectorsFromWayPts.vi	public static Spline.ControlVector[] getCubicControlVectorsFromWaypoints(Pose2d start, Translation2d[] interiorWaypoints, Pose2d end)				
	Χ	Χ	X	X				SplineHelp_GetCubicCtrlVectorsFromWeightedWayPts.vi			_		
	X	X		No				SplineHelp_GetCubicSpline_Calc1.vi		internal			
	X	X		No				SplineHelp_GetCubicSpline_Calc2.vi		internal			
	X	X	X	No				SplineHelp_GetCubicSpline_Calc3.vi	nublic static CubicHormitoSpling	internal			
	X	X		X		X		SplineHelp_getCubicSplinesFromControlVectors.vi	public static CubicHermiteSpline[] getCubicSplinesFromControlVectors(Spline.ControlVector start, Translation2d[] waypoints, Spline.ControlVector end)				
	X	X		X	SI			SplineHelp_GetQuinticCtrlVector.vi	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			
								SplineHelp_GetQuinticCtrlVectorsFromWeightedWayPts.vi		REMOVED 2762			
	X	X		X				SplineHelp_getQuinticSplinesFromControlVectors.vi	public static QuinticHermiteSpline[] getQuinticSplinesFromControlVectors(Spline.ControlVector[] controlVectors)				
	Χ	Χ	X	X				SplineHelp_GetQuinticSplinesFromWeightedWayPts.vi		New 2762			
	Χ	Χ		X				SplineHelp_GetQuinticSplinesFromWayPts.vi		New 2762			
	X	X		No				SplineHelp_ThomasAlgorithm.vi	private static void thomasAlgorithm(double[] a, double[] b, double[c, double[] d, double[] solutionVector)	internal			

Revision 2.X 5/2/2022 – added implicit model follower and time	interp	oolata	able ro	outine	s.				_				
	þ	þ	m		Optimized	90	ogram				Me	m.	king
	Implemente	Documente	Not WPILIB	Meni Item	Execution		Sample Pro				ode Revie	Test Progrä	rror Checi
SPLINE PARAMETERIZER	<u>2</u> X	X	_ <	X		i <u>F</u>		VI Name SplineParam_Spline_T0_T1.vi	Function Prototype public static List <posewithcurvature> parameterize(Spline spline</posewithcurvature>	Notes		<u> </u>	Щ
-									double t0. double t1)				
		X		X		X		SplineParam_Spline.vi	public static List <posewithcurvature> parameterize(Spline spline)</posewithcurvature>				
	X	X	X	N	0			SplineParam_StackGet.vi		internal			
_	X	X	X	N	0			SplineParam_StackPop.vi SplineParam StackPush.vi		internal			
L	^	_ ^		/ / /	0			opilileralalii_otackrusii.vi		internal			
'======= TRAJECTORY '========													
					mized		E						
	þ	þ	m		Onti	e e	ogra				8	ш	ecking
	Implemente	Documente	Vot WPILIB	3			Sample Prog				evie	ogra	Chec
	lem	m	Ŋ	Menu Item	Execution	t RC	nple				ř R	# P	
	lmp	ООС	Not	Me	X X	Tes	San	VI Name	Function Prototype	Notes	S	Test	Error
TRAJECTORY		X		λ				Trajectory_Concatenate.vi					
	X	X		λ		,		Trajectory_equals.vi	boolean equals(other obj)	FUTURE			
	X	X			(S			Trajectory_GetStates.vi Trajectory_GetTotalTime.vi	public List <state> getStates() public double getTotalTimeSeconds()</state>	not needed, use unpack not needed, use unpack			
-	X	X		N				Trajectory_lerp_double.vi	private static double lerp(double startValue, double endValue,	internal			
									double t)				
	X	X		N	o S	/		Trajectory_lerp_Pose.vi	private static Pose2d lerp(Pose2d startValue, Pose2d endValue, double t)	internal			
	Χ				S	ı		Trajectory_New_Empty.vi					
	Χ	X		λ	S	1		Trajectory_New.vi	public Trajectory(final List <state> states)</state>				
	Χ	X		λ				Trajectory_RelativeTo.vi	public Trajectory relativeTo(Pose2d pose)				
	X	X		λ				Trajectory_Sample.vi	public State sample(double timeSeconds)				
	X	X	X	λ				Trajectory_SampleReverse.vi		Sample in reverse order. Negate sample.			
	Χ	X		λ	(Trajectory_TransformBy.vi	public Trajectory transformBy(Transform2d transform)				
									public Pose2d getInitialPose()	can use cluster unpack, array index			
	Implemented	Documented	t WPILIB		Execution Optimized	ue ue	Sample Program				de Review	st Program	or Checking
_			Not				Sai	VI Name	Function Prototype	Notes	Š	7 68	Err
TRAJECTORY_STATE		X			(S	1		TrajectoryState_Equals.vi	boolean equals(other obj)				
		X			S			TrajectoryState_GetAll.vi					
-	X	X			S	1		TrajectoryState_GetPose.vi	Chata intermediate/Chata and Value of subjects				
-	X	X			(S	1		TrajectoryState_Interpolate.vi TrajectoryState_New.vi	State interpolate(State endValue, double i) public State(double timeSeconds, double		-		
	^	^		^	` ``	'		TrajectoryState_ivew.vi	velocityMetersPerSecond, double				
									accelerationMetersPerSecondSq, Pose2d poseMeters, double				
									curvatureRadPerMeter)				
									public State()				

RC LabVIEW Trajectory Library – VI Implementation												
Revision 2.X 5/2/2022 – added implicit model follower and time	interp	oolatal	ole rout	ines.	75							
	plemented	Documented	t WPILIB	Menu Item	ecution Optimizec	Test Routine Sample Program				de Review	st Program	or Checking
	<u>\</u>		Not		Ě	7e		Function Prototype	Notes	ိ	7e	En
TRAJECTORY CONFIG	X	X	~	X	SI SI		TrajectoryConfig_Create.vi TrajectoryConfig_setCentripetalAccel.vi	public TrajectoryConfig(double maxVelocityMetersPerSecond, double maxAccelerationMetersPerSecondSq)				
	X	X	X	X	SI		TrajectoryConfig_setCentripetalAccel.vi TrajectoryConfig_setKinematicsDiffDrive.vi	public TrajectoryConfig setKinematics(DifferentialDriveKinematics				
				^				kinematics)				
	X			X	SI		TrajectoryConfig_setKinematicsMecanumfDrive.vi	public TrajectoryConfig setKinematics(MecanumDriveKinematics kinematics)				
	X	X		X	SI		TrajectoryConfig_setKinematicsSwerveDrive.vi	public TrajectoryConfig setKinematics(SwerveDriveKinematics kinematics)				
	Χ	X		Χ	SI		TrajectoryConfig_setReversed.vi	public TrajectoryConfig setReversed(boolean reversed)				
	Χ	X	Χ	Χ	SI		TrajectoryConfig_setVoltageDiffDrive.vi					
								public TrajectoryConfig addConstraint(TrajectoryConstraint constraint)	Implemented differently, can't duplicate.			
								public TrajectoryConfig addConstraints(List extends<br TrajectoryConstraint> constraints)	Implemented differently, can't duplicate.			
								public double getStartVelocity()	can use cluster unpack			
								public TrajectoryConfig setStartVelocity(double				
								startVelocityMetersPerSecond)				
								public double getEndVelocity() public TrajectoryConfig setEndVelocity(double	can use cluster unpack			
								endVelocityMetersPerSecond)				
								public double getMaxVelocity()	can use cluster unpack			
								public double getMaxAcceleration()	can use cluster unpack			
								public List <trajectoryconstraint> getConstraints()</trajectoryconstraint>	Implemented differently, can't duplicate.			
								public boolean isReversed() NOTE ADD OTHER "SET" ROUTINES FOR OTHER	can use cluster unpack			
								CONTRAINTS HERE, SINCE NEW CONTRAINTS ARE SPECIFIC AND NOT GENERIC.				
	lemented	sumented	WPILIB	nu Item	ecution Optimized	Test Routine Sample Program				de Review	t Program	or Checking
	lmp	ООС	Not	Mer	Exe	Zar Sar	VI Name	Function Prototype	Notes	80	Test	Err
TRAJECTORY GENERATE	X	X		Χ			TrajectoryGenerate_Make_Cubic_CtrlVect.vi	initial. List <translation2d> interiorWaypoints. Spline.ControlVecto</translation2d>	uses cubic splines r			
	Х	Х		X			TrajectoryGenerate_Make_Cubic.vi	end, TrajectoryConfig config) public static Trajectory generateTrajectory(Pose2d start, List <translation2d> interiorWaypoints, Pose2d end,</translation2d>	uses cubic splines			
<u> </u>	X	X	X	Χ			TrajectoryGenerate_Make_Generic.vi	TrajectoryConfig config) Helper to bring these all together	Use this one!!!			
	X	X		X			TrajectoryGenerate_Make_Quintic_CtrlVect.vi	public static Trajectory generateTrajectory(ControlVectorList controlVectors, TrajectoryConfig config)	uses quintic splines			
		Χ	X	Χ			TrajectoryGenerate_Make_Quintic_Weighted.vi	, , , , , , , , , , , , , , , , , , , ,	New 2762			
	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>				
	mplemented	Documented	Not WPILIB	Jenu Item	Execution Optimized	Test Routine Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
TRAJECTORY GENERATE (Control Vector)	-		<	~	W W	<u>~</u> ν.	y vilvallic	public ControlVectorList(int initialCapacity)	may not need, just data		7	Щ
								public ControlVectorList(int initial Capacity) public ControlVectorList()	may not need, just data			

Revision 2.X 5/2/2022 – added implicit model follower and time interpolatable routines. public ControlVectorList(Collection<? extends may not need, just data Spline.ControlVector> collection) Menu Item Function Prototype Notes TRAJECTORY PARAMETERIZE X X TrajectoryParam calcStuffFwd.vi Χ Χ TrajectoryParam calcStuffRev.vi X Χ TrajectoryParam enforceAccel.vi private static void enforceAccelerationLimits(boolean reverse, his routines needs to be changed hen new constraints are added. List<TrajectoryConstraint> constraints, ConstrainedState state) $X \mid X$ Χ No TrajectoryParam enforceVelocity.vi This routines needs to be changed hen new constraints are added. X X public static Trajectory TrajectoryParam_timeParam.vi X timeParameterizeTrajectory(List<PoseWithCurvature> points. List<TrajectoryConstraint> constraints, double startVelocityMetersPerSecond, double endVelocityMetersPerSecond, double maxVelocityMetersPerSecond, double
maxAccelerationMetersPerSecondSq, boolean reversed) Test Routine Menu Item VI Name Function Prototype Notes TRAJECTORY PARAMETERIZE CONSTRAINED STATE X ConstrainedState New.vi ConstrainedState(PoseWithCurvature pose, double distanceMeters, double maxVelocityMetersPerSecond, double minAccelerationMetersPerSecondSq, double maxAccelerationMetersPerSecondSq) X X X X X X X X X X X X X ConstrainedState SetMaxAccel.vi ConstrainedState SetMinAccel.vi ConstrainedState SetVelAccel.vi X X X X ConstrainedState SetVelocity.vi ConstrainedState() Item Function Prototype VI Name Notes TRAJECTORY UTIL X TrajectoryUtil_fromPathWeaverJSON.vi public static Trajectory fromPathweaverJson(Path path) X Χ XX X TrajectoryUtil_MakeWeightedWayPoint_ENG.vi Χ Χ TrajectoryUtil_MakeWeightedWayPoint.vi Χ Χ Χ Χ TrajectoryUtil toPathWeaverJSON.vi public static void toPathweaverJson(Trajectory trajectory, Path public static Trajectory deserializeTrajectory(String json) public static String serializeTrajectory(Trajectory trajectory) Menu Item VI Name Function Prototype Notes TRAPEZOID PROFILE X TrapProfConstraint_New.vi TrapProfile Calculate.vi $X \mid X$

Χ	Χ		No		TrapProfile_Direct.vi	Private, remove from menu
Χ	Χ	Χ	X		TrapProfile_Execute.vi	
Χ	Χ	X	X	SI	TrapProfile_Execute_AtGoal.vi	
Χ	Χ		X		TrapProfile_IsFinished.vi	
Χ	Χ		X		TrapProfile_New_DefInitial.vi	
X	Χ		X		TrapProfile_New.vi	
Χ	Χ		No		TrapProfile_ShouldFlipAcceleration.vi	Private, remove from menu
X	Χ		X		TrapProfile_TimeLeftUntil.vi	
X	Χ		X		TrapProfile_TotalTime.vi	
X	Χ		X		TrapProfState_Equals.vi	
Χ	Χ		X		TrapProfState New.vi	

· ·	X	X		^			TrapProGete Equals.vi	
l	Χ	_ X		Χ			TrapProfState_New.vi	
'=========								
TRAJECTORY CONSTRAINT								
'========					Q			
CENTRIPETAL ACCELERATION CONSTRAINT	X Implemented	X Documented	Not WPILIB	X Menu Item	Execution Optimize	Test Routine	VI Name CentripetalAccelConstraint_getMaxVelocity.vi public double getMaxVelocityMetersPerSecond(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond) CentripetalAccelConstraint_getMinMaxAccel.vi public MinMax	Notes
	^			^			getMinMaxAccelerationMetersPerSecondSq(Pose2d poseMeters,	
							double curvatureRadPerMeter, double velocityMetersPerSecond)	
	X	X		X	SI		CentripetalAccelConstraint_New.vi public CentripetalAccelerationConstraint(double maxCentripetalAccelerationMetersPerSecondSq)	Can use cluster pack for now
DIFF DRIVE KINEMATIC CONSTRAINT	X Implemented	X Documented	Not WPILIB	X Menu Item	So Execution Optimized	Test Routine	VI Name DiffDriveKinematicsConstraint_getMaxVelocity.vi DiffDriveKinematicsConstraint_getMaxVelocity.vi DiffDriveKinematicsConstraint_getMinMaxAccel.vi DiffDriveKinematicsConstraint_getMinMaxAccel.vi DiffDriveKinematicsConstraint_netMinMaxAccel.vi DiffDriveKinematicsConstraint_Netw.vi DiffDriveKinematicsConstraint_Netw.vi DiffDriveKinematicsConstraint_Netw.vi DifferentialDriveKinematics kinematics, double maxSpeedMetersPerSecond)	Notes
DIFF DRIVE VOLTAGE CONSTRAINT	X Implemented	X Documented	Not WPILIB	X Menu Item	Secution Optimized	st Rou	VI Name DiffDriveVoltageConstraint_getMaxVelocity.vi public double getMaxVelocityMetersPerSecond(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond) DiffDriveVoltageConstraint_getMinMaxAccel.vi public MinMax getMinMaxAccelerationMetersPerSecondSq(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond) DiffDriveVoltageConstraint_New.vi public DifferentialDriveVoltageConstraint(SimpleMotorFeedforward feedforward, DifferentialDriveKinematics, double	Notes

JERK CONSTRAINT	/ / Implemented	Documented	X Not WPILIB	Menu Item	Execution Optimized	Test Routine		VI Name JerkConstraint_getMaxVelocity.vi JerkConstraint_getMinMaxAccel.vi JerkConstraint New.vi	Function Prototype Routine exists, it is just a shell Routine exists, it is just a shell	Notes FUTURE FUTURE FUTURE FUTURE
l	/		X		SI			JerkConstraint_New.vi	Routine exists, it is just a shell	FUTURE
MECANUM DRIVE KINEMATICS CONSTRAINT	X X Implemented	X X Documented	Not WPILIB	X Menu Item	Execution Optimized	Test Routine		VI Name MecaDriveKinematicsConstraint_getMaxVelocity.vi MecaDriveKinematicsConstraint_getMinMaxAccel.vi	Function Prototype	Notes
	\hat{X}	$\frac{\hat{x}}{X}$		X	SI			MecaDriveKinematicsConstraint_getwinMaxAccer.vi		
	. Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine		VI Name	Function Prototype	Notes
SWERVE DRIVE KINEMATICS CONSTRAINT	X	X		X				SwerveDriveKinematicsConstraint_getMaxVelocity.vi	public double getMaxVelocityMetersPerSecond(Pose2d poseMeters, double curvatureRadPerMeter, double	
	X	X		X				SwerveDriveKinematicsConstraint_getMinMaxAccel.vi	velocityMetersPerSecond) public MinMax getMinMaxAccelerationMetersPerSecondSq(Pose2d poseMeters, double curvatureRadPerMeter, double velocityMetersPerSecond)	
	Χ	Χ		X	SI			SwerveDriveKinematicsConstraint_New.vi	Newpublic SwerveDriveKinematicsConstraint(final SwerveDriveKinematics kinematics, double maxSpeedMetersPerSecond)	Can use cluster pack for now
TDA IFOTODY CONOTRAINT										
TRAJECTORY CONSTRAINT Interface class - no	thing	done	(not no	eded")					
monace class - no	unig	uonic (1100110	oucu)						
					iized		,			

TRAJECTORY CONSTRAI

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimi	Test Routine	Sample Program	VI Name	Function Prototype	Notes
RAINT (Min Max)	X	X		X	SI			Constraint_MinMax_New.vi	Constraint_MinMax_New	
	Χ	Χ		X	SI			Constraint MinMax NewMinMax VI	Constraint MinMax New	

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UTILITY

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

nd time	interp	olatab	ole rou	ıtines.						
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes
UTIL	Χ	Χ	Χ	X	SI			Util ApproxEqual.vi	, , , , , , , , , , , , , , , , , , ,	
	Χ	Χ	Χ	Χ				Util Array PoseWCurv to XY.vi		
	Χ	Χ	Χ	Χ	SI			Util_CalcDist.vi		
	Χ	Х	Χ	Χ	SI			Util_GetLibraryVersion.vi		
	Χ	X	Χ	Χ	SI			Util_GetLibUsage.vi		
	Х	Х	Х	Х				Util_GetTime.vi		Once tested completely, this should be optimized!
	Χ	Х	Χ	No	N/A			Util_LibraryGlobals.vi		Global Variables – no block diag.
	Χ	Χ	Χ	X				Util Trajectory Absolute To Relative.vi		
	Χ	X	Χ	X				Util_Trajectory_ReadFile.vi		
	Χ	Χ	Χ	X				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	X				Util_Trajectory_WriteFile_PathFinder.vi		
	Χ	Χ	Χ	No				Util_Trajectory_WriteFile_PathFinderConfig.vi		internal
	Χ	Χ	Χ	X				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	Χ				Util_DispWaypoint_Eng_To_SI.vi		
	Χ	Χ	Χ	Χ				Util_DispWaypoint_To_CubicInput.vi		
	Χ	Χ	Χ	X				Util_DispWaypoint_To_QuinticInput.vi		
	Χ	Χ	X	Χ				Util_DispWeightedWaypiont_Eng_To_WeightedWaypoint		
	Χ	Χ	X	No				Util_DispWeightedWayPoint_To_WeightedWayPoint.vi		Sorry about the confusing name

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CONVERSIONS '========

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	Sample Program	VI Name F	Function Prototype	Notes
CONV	Χ	Χ	Χ	Χ	SI			Conv_AngleDegrees_Heading.vi	· · · · · · · · · · · · · · · · · · ·	
	Χ	Χ	Χ	Χ	SI			Conv_AngleRadians_Heading.vi		
	Χ	Χ	Χ	X	SI			Conv_Centimeters_Meters.vi		
	Χ	Χ	Χ	Χ	SI			Conv_Deg_Radians.vi		
	Χ	Χ	Χ	Χ	SI			Conv_Deg_Rotations.vi		
	Χ	Χ	Χ	Χ	SI			Conv_Feet_Meters.vi		
	Χ	Χ	Χ	Χ	SI			Conv_GyroDegrees_Heading.vi		
	Χ	Χ	X	Χ	SI			Conv_Heading_AngleRadians.vi		
	Χ	Χ	Χ	Χ	SI			Conv_Inches_Meters.vi		
	Χ	Χ	X	X	SI			Conv_Kilograms_Pounds.vi		
	X	Χ	Χ	X	SI			Conv_Meters_Feet.vi		
_	X	X	X	X	SI			Conv_Meters_Inches.vi		
	X	X	X	X	SI			Conv_Pose2d_SI_Eng.vi		
-	X	X	X	X	SI			Conv_Pounds_Kilograms.vi		
	X	X	X	X	SI			Conv_Radians_Deg.vi		
	X	X	X	X	SI			Conv_Radians_Rotations.vi		
	X	X	X	X	SI			Conv_Rotations_Deg.vi		
Į	X	Χ	X	X	SI			Conv_Rotations_Radians.vi		

tillio illi	ioi polatar	no roatimos.			
7	/	XX	SI	Conv_Yards_Meters.vi	

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name Function	on Prototype	Notes
UNITS	Χ	Χ		Χ	SI			Units_DegreesToRadians.vi		
	Χ	Χ		Χ	SI			Units_DegreesToRotations.vi		
	Χ	Χ		X	SI			Units_FeetToMeters.vi		
	Χ	Χ		X	SI			Units_InchesToMeters.vi		
	Χ	Χ		X	SI			Units_MetersToFeet.vi		
	Χ	Χ		X	SI			Units_MetersToInches.vi		
	Χ	Χ		X	SI			Units_MillisecondsToSeconds.vi		
	Χ	Χ		X	SI			Units_RadiansPerSecondToRotationsPerMinute.vi		
	Χ	Χ		X	SI			Units_RadiansToDegrees.vi		
	Χ	Χ		X	SI			Units_RadiansToRotations.vi		
	Χ	Χ		X	SI			Units_RotationsPerMinuteToRadiansPerSecond.vi		
	Χ	Χ		Χ	SI			Units_RotationsToDegrees.vi		
	Χ	Χ		Χ	SI			Units_RotationsToRadians.vi		
	Χ	Χ		X	SI			Units_SecondsToMilliseconds.vi		

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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 Optimiz	Test Routine	Sample Program	VI Name Function Prototype	Notes
PATHFINDERUTIL	X	X	X	Χ				PathfinderUtil_Continuous_Heading_Difference.vi	
	X	X	Χ	Χ				PathfinderUtil_OptimizeTrajectoryStates.vi	
	Χ	X	Χ	Χ				PathfinderUtil_ToTrajectory.vi	
	Χ	Χ	Χ	Χ				PathfinderUtil_ToTrajectoryStates.vi	

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STATE SPACE MODEL

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	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	 VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
DC MOTOR	Χ	X		Χ	SI		DCMotor_GetAndymark9015.vi					
	Χ	X		Χ	SI		DCMotor_GetAndymarkRs775_125.vi					
	Χ	X		Χ	SI		DCMotor_GetBag.vi					
	Χ	X		Χ	SI		DCMotor_GetBanebotsRs550.vi					
	Χ	Χ		Χ	SI		DCMotor_GetBanebotsRs775.vi					
	Χ	Χ		Χ	SI		DCMotor_GetCIM.vi					
	Χ	Χ		Χ	SI		DCMotor_GetCurrent.vi					
	Χ	Χ		Χ	SI		DCMotor_GetFalcon500.vi					
	Χ	Χ		Χ	SI		DCMotor_GetMiniCIM.vi					
	Χ	Χ		Χ	SI		DCMotor_GetNEO.vi					
	Χ	Χ		Χ	SI		DCMotor_GetNEO550.vi					

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	Χ	X		Χ	SI	DCMotor_GetRomiBuiltIn.vi			
	Χ	X		Χ	SI	DCMotor_GetVex775Pro.vi			
	Χ	X		Χ	SI	DCMotor_New.vi			
	Χ	X		Χ	SI	DCMotor_PickMotor.vi			

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

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

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

	Implemented	Mot World	Menu Item	Execution Optimi	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
EXTENDED KALMAN FILTER	X X	(X	·		ExtendedKalmanFilter_Correct_OnlyUY.vi					
	X X	(X	·		ExtendedKalmanFilter_Correct.vi		Just a shell, not functional!			
	X X	(X	·		ExtendedKalmanFilter_GetP_Single.vi					
	X X	(X	·		ExtendedKalmanFilter_GetP.vi					
	$X \mid \lambda$	(X			ExtendedKalmanFilter_GetXHat_Single.vi					
	X X	(X	·		ExtendedKalmanFilter_GetXHat.vi					
	X X	(X	·		ExtendedKalmanFilter_New.vi					
	X X	(X			ExtendedKalmanFilter_Predict.vi					
	X X	(X			ExtendedKalmanFilter_Reset.vi					
	$X \mid \lambda$	(X			ExtendedKalmanFilter_SetP.vi					

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FRC LabVIEW Trajectory Library – VI Implementation Revision 2.X 5/2/2022 – added implicit model follower and time	LIST e inte	rnolata	able routi	nes				<u> </u>				
Trovision 2.70 0/2/2022 added implior model follower and time	X	X		X			ExtendedKalmanFilter_SetXHat_Single.vi					
	X	X		X			ExtendedKalmanFilter_SetXHat.vi					
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	nple	Documente	Vot WPILIE	Menu Item		lest Kol	VI Name	Function Prototype	Notes	Code	est	Error
KALMAN FILTER				X .		<u> </u>	KalmanFilter_Correct.vi	i unction i rototype	Notes			Щ
	X	Χ		X			KalmanFilter_GetK					
	X			X X			KalmanFilter_GetK_Single.vi KalmanFilter_GetXHat					
	X			X	j	X	KalmanFilter_GetXHaT_Single					
	X	X		X)	X	KalmanFilter_New.vi					
	X			X X	(X	KalmanFilter_Predict.vi KalmanFilter Reset.vi					
	X		+	X			KalmanFilter_Reset.vi KalmanFilter_SetXHat					
	X			Х)	X	KalmanFilter_SetXHat_Single					
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	Jmp	Doc) I	Se /		Function Prototype	Notes	Code	Test	Erre
KALMAN FILTER LATENCY COMPENSATOR				X			KalmanFilterLatencyComp_AddObserverState.vi					
	X	X		X			KalmanFilterLatencyComp_ApplyPastGlobalMeas_FuncGroup.	VI				
	X	X		Х			KalmanFilterLatencyComp_ApplyPastGlobalMeasurement_UKI	vi				
	X	X	+	X			KalmanFilterLatencyComp_FindClosestMeasurement.vi					
	X	Χ		X			KalmanFilterLatencyComp_New.vi					
	X	X	+	X			KalmanFilterLatencyComp_Observer_New.vi KalmanFilterLatencyComp_Reset.vi					
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MECANUM DRIVE POSE ESTIMATOR		<u>~</u> ~_		ع ز	<u> </u>	3 4	VI Name MecaDrivePoseEst_AddVisionMeasurement_StdDev.vi	Function Prototype	Notes	Š		<u> </u>
MECANUM DRIVE POSE ESTIMATOR		X	+	X			MecaDrivePoseEst_AddVisionMeasurement.vi					
	X	X		Χ			MecaDrivePoseEst_GetEstimatedPosition.vi					
	X		+	No No			MecaDrivePoseEst_Kalman_F_Callback.vi MecaDrivePoseEst_Kalman_H_Callback.vi					
	X		+ + + '	X			MecaDrivePoseEst_Raiman_n_Caliback.vi MecaDrivePoseEst_New.vi					
	X	X		X			MecaDrivePoseEst_ResetPosition.vi					
	X			X X			MecaDrivePoseEst_SetVisionMeasurementStdDevs.vi MecaDrivePoseEst_Update.vi				<u> </u>	
	X			X			MecaDrivePoseEst_UpdateWithTime.vi					
	X	X		No			MecaDrivePoseEst_VisionCorrect_Callback.vi					
	X	X	+	No			MecaDrivePoseEst_VisionCorrect_Kalman_H_Callback.vi				<u> </u>	
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Revision 2.X 5/2/2022 – added implicit model follower and time		olatab	ole rou	tines.	_							
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	X			X			SwerveDrivePoseEst_SetVisionMeasurementStdDevs.vi					
	X			X			SwerveDrivePoseEst_Update.vi					
				X			SwerveDrivePoseEst_UpdateWithTime.vi					
	X			X			SwerveDrivePoseEst_VisionCorrect_Callback.vi					
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UNSCENTED KALMAN FILTER	X	×		X			UnscentedKalmanFilter_Correct_OnlyUY.vi					
	X	^		X			UnscentedKalmanFilter Correct OnlyUYR.vi					
				X			UnscentedKalmanFilter Correct.vi					
				X			UnscentedKalmanFilter_GetP_Single.vi					
	X			X			UnscentedKalmanFilter GetP.vi					
	X			X			UnscentedKalmanFilter_GetXHat_Single.vi					
	X			X			UnscentedKalmanFilter GetXHat.vi					
				Х			UnscentedKalmanFilter_New_Default.vi					
	X			X			UnscentedKalmanFilter_New_FuncGroup.vi					
	X			X			UnscentedKalmanFilter_New.vi					
		Χ		X			UnscentedKalmanFilter_Predict.vi					
				X			UnscentedKalmanFilter_Reset.vi					
	X	X		X			UnscentedKalmanFilter_SetP.vi					
	X			X			UnscentedKalmanFilter_SetXHat_Single.vi					
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DIFFERENTIAL DRIVE ACCELERATION LIMITE	$\frac{X}{X}$		 	X		X	DiffDrvAccelLimit_Calculate.vi DiffDrvAccelLimit_New.vi					
	nted	ited		tem >	ion Optimized		PurpryAccelTimit_idem.vi			Review	rogram	1
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	Χ			Χ		Χ	ImplModelFollow_GetU_Single.vi					
	X		 	X		X	ImplModelFollow_New.vi					
	X	_		X		X	ImplModelFollow_New_Plant.vi ImplModelFollow_Reset.vi					
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	X			X			LinearPIntInvFF_GetUff.vi					
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	X			X			LinearPIntInvFF_New.vi					
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LINEAR QUADRATIC REGULATO	R X X	X X X		X	Execution		VI Name LinearQuadraticRegulator_Calculate_NextR.vi LinearQuadraticRegulator_Calculate.vi LinearQuadraticRegulator_GetK Single.vi	Function Prototype	Notes NOT ORIGINAL	Code Review		
LINEAR QUADRATIC REGULATO	X X X X	X X X X		X X X	Execution	X Test Routine	VI Name LinearQuadraticRegulator_Calculate_NextR.vi LinearQuadraticRegulator_Calculate.vi LinearQuadraticRegulator_GetK_Single.vi LinearQuadraticRegulator_GetK.vi	Function Prototype		Code Review		
LINEAR QUADRATIC REGULATO	X X X X X X X X X X	X X X X		X X X	Execution		VI Name LinearQuadraticRegulator_Calculate_NextR.vi LinearQuadraticRegulator_Calculate.vi LinearQuadraticRegulator_GetK_Single.vi LinearQuadraticRegulator_GetK.vi LinearQuadraticRegulator GetR Single.vi	Function Prototype		Code Review		
LINEAR QUADRATIC REGULATO	R	X X X X X X		X X X	Execution		VI Name LinearQuadraticRegulator_Calculate_NextR.vi LinearQuadraticRegulator_Calculate.vi LinearQuadraticRegulator_GetK_Single.vi LinearQuadraticRegulator_GetK.vi LinearQuadraticRegulator_GetR_Single.vi LinearQuadraticRegulator_GetR_Single.vi LinearQuadraticRegulator_GetR.vi LinearQuadraticRegulator_GetU_Single.vi	Function Prototype		Code Review		
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oder follower and time	e miler p	บเลเลม	e rouli	ies.									
	X	X		X		Χ		LinearQuadraticRegulator_New_SystemELMS.vi					
	X	X		Χ				LinearQuadraticRegulator_New.vi					
	X	X		Χ				LinearQuadraticRegulator_Reset.vi					
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name F	Function Prototype	Notes	Code Review	Test Program	Error Checking
LINEAR SYSTEM	X	Χ		X	1			LinearSystem_CalculateX.vi					
	X	X		Χ	- 1			LinearSystem_CalculateY.vi					
	X	X		Χ	SI			LinearSystem_GetA.vi					
	X	X		Χ	SI			LinearSystem_GetAElement.vi					
	X	X		Χ	SI			LinearSystem_GetB.vi					
	X	X		Χ	SI			LinearSystem_GetBElement.vi					
	X	X		X	SI			LinearSystem_GetC.vi					
	X	X		X	SI			LinearSystem_GetCElement.vi					
	X	X		X	SI			LinearSystem_GetD.vi					
	Χ	Χ		Χ	SI			LinearSystem_GetDElement.vi					
	Χ	Χ		Χ	SI			LinearSystem_New.vi					

	Implemented	Documented	мепи пет	Execution Optimized	Test Routine	Egy VI Name Function Prototype	Notes	Code Review	Test Program	Error Checking
LINEAR SYSTEM LOOP		Χ	X			LinearSystemLoop_ClampInput.vi				
	Χ	Χ	 X			LinearSystemLoop_Correct.vi				
						LinearSystemLoop_GetClampFunction.vi				
	X	X	 X			LinearSystemLoop_GetController.vi				
	X	X	 X X			LinearSystemLoop_GetError_Single.vi				
•	X		X X			LinearSystemLoop_GetError.vi				
•	X	X	X X			LinearSystemLoop_GetFeedForward.vi				
•	X	X	X			LinearSystemLoop_GetNextR_Single.vi LinearSystemLoop_GetNextR.vi				
	\hat{x}	$\stackrel{\wedge}{X}$	X			LinearSystemLoop_GetNextr.vi LinearSystemLoop_GetObserver.vi				
	\hat{x}	X	X			LinearSystemLoop_GetU_Row.vi				
	X	X	X			LinearSystemLoop_GetU.vi				
	X	X	X			LinearSystemLoop_GetXHat_Single.vi				
	X	X	×			LinearSystemLoop_GetXHat.vi				
						LinearSystemLoop New BBB				
						LinearSystemLoop_New_LinearSystem_ClampFunc				
	Χ	Х	X			LinearSystemLoop_New_LinearSystem_ClampVal.vi				
	Χ	Χ	X			LinearSystemLoop_New.vi				
	Χ	Χ	X			LinearSystemLoop_Predict.vi				
	Χ	Χ	X			LinearSystemLoop_Reset.vi				
						LinearSystemLoop_SetClampFunction.vi				
						LinearSystemLoop_SetNextR_Some.vi				
	Χ	Χ	X			LinearSystemLoop_SetNextR.vi				
						LinearSystemLoop_SetXHat_Single.vi				
						LinearSystemLoop_SetXHat.vi				

FRC LabVIEW Trajectory Library – VI Implementation	List						_				
Revision 2.X 5/2/2022 – added implicit model follower and time	e interpo	olatable	e routine	϶s. Φ							
LTV DIFFERENTIAL DRIVE CONTROLLER	X X X Implemented	Documented)))	X X X Menu Item Execution Optimize	Test Routine	VI Name LTVDiffDriveCtrl_Calculate.vi LTVDiffDriveCtrl_New.vi LTVDiffDriveCtrl_Calculate_TrajState.vi LTVDiffDriveCtrl_Calculate_SetTolerance.vi LTVDiffDriveCtrl_Calculate_AtReference.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
	Implemented	Documented	Not W	Menu Item Execution Optimized	Test Routine		Function Prototype	Notes	Code Review	Test Program	Error Checking
LTV UNICYCLE CONTROLLER	X			X X	X			This one computes a new LQR			
	X		X		X			each time. This one computes a new LQR each time.			
	X			X	X			each ume.			
	X			X X	X						
	X		>	Χ	Х	LTVUnicycleCtrl_SetEnabled.vi					
	Χ		>	X	X	LTVUnicycleCtrl_SetTolerance.vi					_
'======= STATE SPACE UTILITIES '=========											
CALLBACK HELPER	X X X	X X X Documented	X	X X X	Test Routine	VI Name CallbackHelp_MatrixMinus.vi CallbackHelp_MatrixMult_CoerceSizeB.vi CallbackHelp_MatrixMult.vi CallbackHelp_MatrixPlus.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
DISCRETIZATION	X X X	X X X))	X X X Menu Item Execution Optimized	X X X Test Routine	VI Name Discretization_DiscretizeA.vi Discretization_DiscretizeAB.vi Discretization_DiscretizeABTaylor.vi Discretization_DiscretizeAQ.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
				X	X						
	X	X		X	+	Discretization_DiscretizeR.vi					

STATE SPACE UTIL	X Implemented	X Documented	X Not WPILIB	od Menu Item	Execution Optimized	Test Routine	E B B B B B B B B B B B B B B B B B B B	Function Prototype	Notes Internal routine	Code Review	Test Program	Error Checking
	X	Χ		Χ			StateSpaceUtil_ClampInputMaxMagnitude.vi		Routine exists, it is just a shell			
	Χ	Χ		Χ			StateSpaceUtil_IsDetectable.vi					
	X	X		Χ			StateSpaceUtil_IsStabalizable.vi					
	Χ	Χ		X		Χ	StateSpaceUtil_MakeCostMatrix.vi					
	X	Χ		X		Χ	StateSpaceUtil_MakeCovarianceMatrix.vi					
	X	X		X			StateSpaceUtil_MakeWhiteNoiseVector.vi					
	Χ	Χ		X			StateSpaceUtil_NomalizeInputVector.vi					
	X	X		Χ			StateSpaceUtil_PoseTo3dVector.vi					
	Χ	Χ		Χ			StateSpaceUtil_PoseTo4dVector.vi					
	X	X		Χ			StateSpaceUtil_PoseToVector.vi					
										'		

'======= SIMULATION '========

BATTERY SIM	X Implemented	X X Documented	Not WPILIB	X Menu Item	ত ত Execution Optimized	Test Routine	VI Name BatterySim_CalculateDefaultBatteryLoadedVoltage.vi BatterySim_CalculateLoadedVoltage.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
DC MOTOR SIM	X X Implemented	X X Documented	Not WPILIB	X X Menu Item	Execution Optimized	Test Routine	VI Name DCMotorSim_getAngularPositionRad.vi DCMotorSim_getAngularPositionRotations.vi DCMotorSim_getAngularVelocityRadPerSec.vi DCMotorSim_getAngularVelocityRPM.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
	X X X X	X X X X		X X X X X			DCMotorSim_getAngularVelocityRPM.vi DCMotorSim_GetCurrentDrawAmps.vi DCMotorSim_New_MOl.vi DCMotorSim_New_Plant.vi DCMotorSim_SetInputVoltage.vi DCMotorSim_Update.vi					
DIFFERENTIAL DRIVE TRAIN SIM	X X Implemented	X X Documented	Not WPILIB	X Wenu Item	Execution Optimized	Test Routine	VI Name DiffDriveTrainSim_ClampInput.vi DiffDriveTrainSim_CreateKitbotSim_EstMass.vi DiffDriveTrainSim_CreateKitbotSim_EstMassMOI.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking

	X		X				ElevatorSim GetPositionMeters.vi ElevatorSim GetVelocityMetersPerSecond.vi ElevatorSim HasHitLowerLimit.vi ElevatorSim HasHitUpperLimit.vi ElevatorSim New LinSys NoNoise.vi ElevatorSim New LinSys.vi ElevatorSim New NoNoise.vi ElevatorSim New.vi ElevatorSim New.vi ElevatorSim RKF45 Func.vi ElevatorSim SetInputVoltage.vi ElevatorSim SetState.vi ElevatorSim Update.vi ElevatorSim UpdateX.vi ElevatorSim WouldHitLowerLimit.vi ElevatorSim WouldHitUpperLimit.vi		Needed because this doesn't extend.			
	X		X				ElevatorSim GetPositionMeters.vi ElevatorSim GetVelocityMetersPerSecond.vi ElevatorSim HasHitLowerLimit.vi ElevatorSim HasHitUpperLimit.vi ElevatorSim New LinSys_NoNoise.vi ElevatorSim New NoNoise.vi ElevatorSim New NoNoise.vi ElevatorSim New.vi ElevatorSim RKF45_Func.vi ElevatorSim SetInputVoltage.vi ElevatorSim SetState.vi ElevatorSim_Update.vi ElevatorSim_UpdateX.vi ElevatorSim_WouldHitLowerLimit.vi					
	X		X X X X No X X X				ElevatorSim GetPositionMeters.vi ElevatorSim GetVelocityMetersPerSecond.vi ElevatorSim HasHitLowerLimit.vi ElevatorSim New LinSys_NoNoise.vi ElevatorSim New LinSys.vi ElevatorSim New NoNoise.vi ElevatorSim New NoNoise.vi ElevatorSim New.vi ElevatorSim RKF45_Func.vi ElevatorSim SetInputVoltage.vi ElevatorSim SetState.vi ElevatorSim_Update.vi					
	X		X X X X No X X X				ElevatorSim GetPositionMeters.vi ElevatorSim GetVelocityMetersPerSecond.vi ElevatorSim HasHitLowerLimit.vi ElevatorSim New LinSys_NoNoise.vi ElevatorSim New LinSys.vi ElevatorSim New NoNoise.vi ElevatorSim New NoNoise.vi ElevatorSim New.vi ElevatorSim RKF45_Func.vi ElevatorSim SetInputVoltage.vi ElevatorSim SetState.vi ElevatorSim_Update.vi					
	X X X X X X X X X X X X X X X X X X X		X X X X No X X				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi ElevatorSim_HasHitLowerLimit.vi ElevatorSim_HasHitUpperLimit.vi ElevatorSim_New_LinSys_NoNoise.vi ElevatorSim_New_LinSys.vi ElevatorSim_New_NoNoise.vi ElevatorSim_New.vi ElevatorSim_New.vi ElevatorSim_RKF45_Func.vi ElevatorSim_SetInputVoltage.vi ElevatorSim_SetState.vi					
	X X X X X X X X X X X X X X X X X X X		X X X X No				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi ElevatorSim_HasHitLowerLimit.vi ElevatorSim_HasHitUpperLimit.vi ElevatorSim_New_LinSys_NoNoise.vi ElevatorSim_New_LinSys.vi ElevatorSim_New_NoNoise.vi ElevatorSim_New_NoNoise.vi ElevatorSim_New.vi ElevatorSim_RKF45_Func.vi ElevatorSim_SetInputVoltage.vi					
	X		X X X X No				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi ElevatorSim_HasHitLowerLimit.vi ElevatorSim_HasHitUpperLimit.vi ElevatorSim_New_LinSys_NoNoise.vi ElevatorSim_New_LinSys.vi ElevatorSim_New_NoNoise.vi ElevatorSim_New_NoNoise.vi ElevatorSim_New.vi ElevatorSim_New.vi					
	X X X X X	(X X X				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi ElevatorSim_HasHitLowerLimit.vi ElevatorSim_HasHitUpperLimit.vi ElevatorSim_New_LinSys_NoNoise.vi ElevatorSim_New_LinSys.vi ElevatorSim_New_NoNoise.vi ElevatorSim_New_NoNoise.vi					
	X X X X X	(X X X				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi ElevatorSim_HasHitLowerLimit.vi ElevatorSim_HasHitUpperLimit.vi ElevatorSim_New_LinSys_NoNoise.vi ElevatorSim_New_LinSys.vi ElevatorSim_New_NoNoise.vi					
	X X	(X				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi ElevatorSim_HasHitLowerLimit.vi ElevatorSim_HasHitUpperLimit.vi ElevatorSim_New_LinSys_NoNoise.vi ElevatorSim_New_LinSys.vi					
	X X	(X				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi ElevatorSim_HasHitLowerLimit.vi ElevatorSim_HasHitUpperLimit.vi ElevatorSim_New_LinSys_NoNoise.vi					
	X X	(X				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi ElevatorSim_HasHitLowerLimit.vi					
	X	(X				ElevatorSim_GetPositionMeters.vi ElevatorSim_GetVelocityMetersPerSecond.vi					
			X				ElevatorSim_GetPositionMeters.vi					
ELEVATOR SIM			X				ElevatorSim GetCurrentDraw.vi		İ			
			<u>×</u>	Щ	7e	Sa		Function Prototype	Notes		7e	Ē
	Implemented	Not WPILIB	Menu Item	Execution	Test Routine	Sample				Code Revie	sst F	Error
	пеп	12	Iten	rtion	Rout	le P				Rev	rog	Che
	ted	9	,	ď	ine	Program				iew	ram	Checking
				timi;		am						B
				pəz								
	X	(X				DiffDriveTrainSim_Update.vi					
	X X		X				DiffDriveTrainSim_ToughBoxMiniMotor.vi					
	X	(X				DiffDriveTrainSim_ToughBoxMiniGearRatio.vi					
	X		X				DiffDriveTrainSim_SetState.vi					
	X X		X				DiffDriveTrainSim_SetInputs.vi					
	XXX		X				DiffDriveTrainSim_SetCurrentGearing.vi DiffDriveTrainSim SetInputs.vi					
	X		X				DiffDriveTrainSim_New.vi					
	X	(X				DiffDriveTrainSim_New_Mass_MOI.vi					
	X		X				DiffDriveTrainSim KitBotWheelSize.vi					
	X		X				DiffDriveTrainSim GetState_vi					
	XXX		X				DiffDriveTrainSim_GetState_Single.vi					
	XXX		X				DiffDriveTrainSim_GetRightPositionMeters.vi DiffDriveTrainSim_GetRightVelocityMetersPerSecond.vi					
	X X		X				DiffDriveTrainSim_GetRightCurrentDrawAmps.vi					
	X	(X				DiffDriveTrainSim_GetPose.vi					
	X		X				DiffDriveTrainSim_GetOutput_Single.vi					
	$\begin{array}{ c c c c c c c c c c c c c c c c c c c$		X				DiffDriveTrainSim_GetLeftVelocityMetersPerSecond.vi					
	X X		X				DiffDriveTrainSim_GetLeftCurrentDrawAmps.vi DiffDriveTrainSim_GetLeftPositionMeters.vi					
	XX		X				DiffDriveTrainSim_GetHeading.vi					
	X X		X				DiffDriveTrainSim_GetDynamics.vi					
	X		Χ				DiffDriveTrainSim_GetCurrentGearing.vi					
	X		X				DiffDriveTrainSim_GetCurrentDrawAmps.vi					
		(X				DiffDriveTrainSim CreateKitbotSim.vi					

FRC LabVIEW Trajectory Library – VI Implementation	l ist											
Revision 2.X 5/2/2022 – added implicit model follower and time		polatal	ble routi	ines.				_				
·							FlyWheelSim_New_LinSys_NoNoise		Future			
	X	X		X			FlyWheelSim_New_MOI.vi					<u> </u>
	X			X X			FlyWheelSim_SetInput.vi FlyWheelSim_SetState.vi					
	X			X			FlyWheelSim_Update.vi			+ +		
LINEAR SYSTEM SIM	X	X		X X X	Execution Optimized	Sample Program	VI Name LinearSystemSim_ClampInput.vi LinearSystemSim_GetCurrentDrawAmps.vi LinearSystemSim_GetOutput_Single.vi LinearSystemSim_GetOutput.vi	Function Prototype	Notes DONT IMPLEMENT	Code Review	Test Program	Error Checking
	Χ	Χ		Χ			LinearSystemSim_New LinearSystemSim_New_NoNoise.vi					
	X	Х		Х			LinearSystemSim_SetInput_Array.vi		Doesn't use clamp ?	+		<u> </u>
	Χ	Χ		X			LinearSystemSim_SetInput_Single.vi		·			
	Χ			Χ			LinearSystemSim_SetInput.vi					
	X			X			LinearSystemSim_Setstate.vi					į
	X			X No			LinearSystemSim_Update.vi LinearSystemSim_UpdateX.vi					<u> </u>
	X	X		No			LinearSystemSim_UpdateY.vi					
SINGLE JOINT ARM SIM	X X X X X X X X X X X X X X X X X X X	X		X X X X X X X X X X X X X X X X X X X	Execution Optimized	Sample Program	VI Name SngJntArmSim_EsitmateMOI.vi SngJntArmSim_GetAngleRads.vi SngJntArmSim_GetCurrentDraw.vi SngJntArmSim_GetVelocityRadsPerSec.vi SngJntArmSim_HasHitLowerLimit.vi SngJntArmSim_HasHitUpperLimit.vi SngJntArmSim_New.vi SngJntArmSim_Rkf45_Func.vi SngJntArmSim_SetInputVoltage.vi SngJntArmSim_SetState.vi SngJntArmSim_Update.vi SngJntArmSim_UpdateX.vi SngJntArmSim_WouldHitLowerLimit.vi SngJntArmSim_WouldHitLowerLimit.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
MATRIX UTILITIES '========												
MAT BUILDER	× Implemented	× Documented	Not WPILIB		© Execution Optimized	Sample Program	VI Name MatBuilder Create.vi	Function Prototype	Notes	Code Review	Test Program	Error Checking
	^_	_ ^	1	^	JI		watbulluci_Oreate.vi					
FRC_LabVIEW_Trajectory_Library_Routines.xlsx												Page 31 / 3

		X	10 100	X	SI		MatBuilder_Fill.vi					
							· <u> </u>					
	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
MATRIX	Χ	Χ		X	SI		Matrix_AssignBlock.vi					
	Χ	Χ		Χ	SI		Matrix_Block.vi					
_	V	V		Χ	SI		Matrix_ChangeBoundsUnchecked.vi Matrix_Create.vi					
	X	X		_ X	31		Matrix Det.vi					
	X	X		X	SI		Matrix_Diag.vi					
				- , ,	<u> </u>		Matrix Div Scalar.vi		labview has function			
							Matrix ElementPower.vi					
	Χ	Χ		Χ	SI		Matrix_ElementSum.vi					
							Matrix_ElementTimes.vi					
		\ <u>\</u>			,		Matrix_Equals.vi					
	X	X		X	SI		Matrix_Exp.vi Matrix ExtractColumnVector.vi					
-		\hat{X}		X	SI		Matrix ExtractFrom.vi					
					, O,		Matrix ExtractMatrix.vi					
	X	X		X	SI		Matrix_ExtractRowVector.vi					
		Χ		Χ	SI		Matrix_Fill.vi					
							Matrix_Get.vi		labview has function			
	Χ	Χ		Χ	1		Matrix_Ident.vi		WPILIB calls this EYE			
_	X	V		V	SI		Matrix_Inv.vi					
	^	^		_ X	31		Matrix_IsEqual.vi Matrix_IsIdentical.vi					
	X	X		X	,		Matrix_LLTDecompose.vi					
							Matrix Max.vi					
							Matrix_MaxAbs.vi					
							Matrix_Mean.vi					
							Matrix_MinInternal.vi					
_							Matrix_Minus_Matrix.vi					
_	X	X		X	1		Matrix_Minus_Scalar.vi Matrix_NormF.vi					
-	^	^		^			Matrix NormIndP1.vi					
							Matrix_Plus_Matrix.vi					
							Matrix_Plus_Scalar.vi					
	Χ	Χ		Χ	1		Matrix_Pow.vi		THIS NEEDS WORK!!!!			
	Χ	Χ		Χ	SI		Matrix_SetColumn.vi					
	X	X		X	SI		Matrix_SetRow.vi	THERE ARE LOTS OF OTHER MATRIX FUNCTIONS THAT SHOULD BE INCLUDED HERE FOR ISOLATION.				
							Matrix Solve.vi	SHOOLD BE INCLUDED HEIZE FOR ISOLATION.				
							Matrix_Times_Matrix.vi					
							Matrix_Times_Scalar.vi					
							Matrix_Trace.vi					
_		Χ	X	X	SI		Matrix_Transpose.vi Matrix_WithinTolerance.vi					
-	Χ			^			iviatrix_vvitriiir i olerance.vi					
	mplemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	VI Name			Code Review	t Program	Error Checking
	du,	200	Vot	Ver	ii Xe	Tes	VI Name	Function Prototype	Notes	80	Tes	Ξrrc
SIMPLE MATRIX	X	X		X	SI		SimpleMatrix_ExtractMatrix.vi		NOTE Matrix also has an ExtractMatrix with different calling parameters YUK.		17	<i>F</i>

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program	VI Name	Function Prototype	Notes	Code Review	Test Program	Error Checking
MATRIX HELPER	X	Χ	X	X	SI			MatrixHelper_CooerceSize.vi					
	Χ	Χ	Χ	Χ	SI			MatrixHelper_MultCooerceBSize.vi					
	Χ	Χ	Χ	Χ	SI			MatrixHelper_Zero.vi					

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine		Function Prototype	Notes	Code Review	Test Program	Error Checking
VECTOR BUILDER	Χ	X		Χ	SI		VecBuilder_1x1Fill.vi					
	Χ	Χ		X	SI		VecBuilder_2x1Fill.vi					
	Χ	X		Χ	SI		VecBuilder_3x1Fill.vi					
	Χ	Χ		Χ	SI		VecBuilder_4x1Fill.vi					
	Χ	Χ		Χ	SI		VecBuilder_5x1Fill.vi					
	Χ	X		Χ	SI		VecBuilder_6x1Fill.vi					
	Χ	Χ		Χ	SI		VecBuilder_7x1Fill.vi					
	Χ	X		Χ	SI		VecBuilder_8x1Fill.vi					
							VecBuilder_9x1Fill.vi					
							VecBuilder_10x1Fill.vi					
	Χ	Χ	Χ	Χ	SI		VecBuilder_ArrayBy1Fill.vi					

'========= MATH '========

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program Program	Function Prototype	Notes	Code Review	Test Program	Error Checking
ANGLE STATISTICS	X	X	X	Χ	X		AngleStats_AngleAdd_CallbackHelp.vi					
	Χ	X		X	1	X	AngleStats_AngleAdd.vi					
	X	X	X	X	X		AngleStats_AngleMean_CallbackHelp.vi					
	Χ	X		X	1	X						
	Χ	X	X	X	X		AngleStats_AngleResidual_CallbackHelp.vi					
	X	X		X	1	X						

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program emple Program	Function Prototype Notes	Code Review	Test Program	Error Checking
MATH UTILITY	X	Χ		Χ	SI		MathUtil_AngleModulus.vi				
	Χ	X		X	SI		MathUtil_ApplyDeadband.vi				
	X	Χ		Χ	SI		MathUtil Clamp Int.vi				

added implicit model follower and time	inter	olata	ble rou	tines.								
	Χ	X		X	SI			MathUtil_Clamp.vi				
	X	X		Χ	SI			MathUtil_InputModulus.vi				
	Χ	X		Χ	Si			MathUtil_Interpolate.vi				
MERWE SCALED SIGMA POINTS		X Documented	Not WPILIB	X Menu Item	- Execution Optimized	Test Routine	Sample Program	VI Name Function Prototype MerweScSigPts_ComputeWeights.vi	Notes	Code Review	Test Program	Error Checking
	X	X		X	SI			MerweScSigPts_GetNumSigmas.vi				
	X	X		X	SI			MerweScSigPts_GetWc_Single.vi				
	Χ	X		Χ	SI			MerweScSigPts_GetWc.vi				
	Χ	Χ		Χ	SI			MerweScSigPts_GetWm_Single.vi				
	Χ	X		Χ	SI			MerweScSigPts_GetWm.vi				
	Χ	X		X	1			MerweScSigPts_New_Default.vi				
	Χ	Χ		Χ	1			MerweScSigPts_New.vi				
	Χ	Χ		Χ	1			MerweScSigPts_SigmaPoints.vi				
	mplemented	Documented	Not WPILIB	Menu Item	Execution Optimize	Test Routine	Sample Program	VI Name Function Prototype	Notes	Code Review	Test Program	Error Checking
NUMERICAL INTEGRATION	X	X		_ <u><</u>	<u> </u>	_		NumIntegrate_Func_Ax_Bu_K.vi	NOT USED. Should this be used			
NOMERICAL INTEGRATION	_ ^	^		^	'			ivuillinegrate_i une_co_bu_ivi	or abandoned???			
	X	X		Χ				NumIntegrate_Rk4_Dbl_X_U.vi	or abandoned: : :			
	X	X		X				NumIntegrate_Rk4_Dbl_X.vi				
	X	X		X				NumIntegrate_Rk4_Mat_X_U.vi				
	X	X		X		_		NumIntegrate_Rk4_Mat_X.vi				
	X	X		No	SI	1		NumIntegrate_Rkdp_Func_A.vi				
	X	X		No	SI			NumIntegrate_Rkdp_Func_B1.vi				
	X	X		No	SI			NumIntegrate_Rkdp_Func_B1B2.vi				
	X	X		No	SI			NumIntegrate_Rkdp_Func_B2.vi				
	X	X		No	1	†		Numintegrate_Rkdp_Impl.vi				
	X	X		Χ				NumIntegrate_RKDP_Mat_X_U.vi	New replacement for RKF45			
	X	Χ		No	SI			NumIntegrate_Rkf45_Func_A.vi				
	X	X		No	SI			NumIntegrate_Rkf45_Func_B1.vi				
	Χ	Χ		No	SI			NumIntegrate_Rkf45_Func_B1B2.vi				
	X	X		No	SI			NumIntegrate_Rkf45_Func_B2.vi				
	_ ^				, O,							
								NumIntegrate_RKf45_Func_Bs.vi	Removed. Replaced with newer functions.			
	^							NumIntegrate_RKf45_Func_Bs.vi NumIntegrate_RKf45_Func_Ch.vi	functions. Removed. Replaced with newer functions.			
								NumIntegrate_RKf45_Func_Bs.vi NumIntegrate_RKf45_Func_Ch.vi NumIntegrate_RKf45_Func_Ct.vi	functions. Removed. Replaced with newer			
	X	X		No				NumIntegrate_RKf45_Func_Bs.vi NumIntegrate_RKf45_Func_Ch.vi NumIntegrate_RKf45_Func_Ct.vi NumIntegrate_Rkf45_Impl.vi	functions. Removed. Replaced with newer functions. Removed. Replaced with newer functions.			
				No X				NumIntegrate_RKf45_Func_Bs.vi NumIntegrate_RKf45_Func_Ch.vi NumIntegrate_RKf45_Func_Ct.vi NumIntegrate_Rkf45_Impl.vi NumIntegrate_Rkf45_Mat_X_U.vi	functions. Removed. Replaced with newer functions. Removed. Replaced with newer functions. Note that this Feinberg method has been changed and a Dormand Price method has been implemented TODO			
	X X	X X	X	X	I			NumIntegrate_RKf45_Func_Bs.vi NumIntegrate_RKf45_Func_Ch.vi NumIntegrate_RKf45_Func_Ct.vi NumIntegrate_Rkf45_Impl.vi NumIntegrate_Rkf45_Mat_X_U.vi NumIntegrate_RKf45_New.vi	functions. Removed. Replaced with newer functions. Removed. Replaced with newer functions. Note that this Feinberg method has been changed and a Dormand Price method has been			
	X	X X	X	X	I			NumIntegrate_RKf45_Func_Bs.vi NumIntegrate_RKf45_Func_Ch.vi NumIntegrate_RKf45_Func_Ct.vi NumIntegrate_Rkf45_Impl.vi NumIntegrate_Rkf45_Mat_X_U.vi	functions. Removed. Replaced with newer functions. Removed. Replaced with newer functions. Note that this Feinberg method has been changed and a Dormand Price method has been implemented TODO			

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VISION
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Riccati Input Check.vi

| Particular Protection Prototype | Notes | Particular Prototype | Notes | Particular Prototype | Notes | Particular Prototype | Particular Prototype | Notes | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype | Particular Prototype |

'====== TYPE DEFINITIONS '=======

	Implemented	Documented	Not WPILIB	Menu Item	Execution Optimized	Test Routine	Sample Program			
	dul	Рос	Not	Mer	Exe	Tesi	San	VI Name	Function Prototype	Notes
TypeDef		Χ	Χ	Χ	N/A			ARM_FF.CTL		
	Ζ	Χ	Χ	Χ	N/A			BANG_BANG.CTL		
	ı		X	X	N/A			BICon-Matrix_FUNC_TYPE.CTL		NOT USED. Should this be deleted or abandoned???
	<u> </u>	X	X	X	N/A			CALLBACK_FUNC_TYPE.CTL		
	Z	X	X	X	N/A N/A			CHASSIS_SPEEDS.CTL CONTRAINED STATE.CTL		
	Z	X	X	X	N/A N/A			COORDINATE AXIS.CTL		
	Z	^	X	X	N/A			COORDINATE_AXIO.CTL		
	Z	Х	X	X	N/A			DCMOTOR TYPES ENUM.CTL		
	Ζ	Χ	Χ	Χ	N/A			DCMOTOR.CTL		
	Ζ	Χ	Χ	Χ	N/A			DCMOTOR_SIM.CTL		
	Ζ	Χ	Χ	Χ	N/A			DEBOUNCER_TYPE_ENUM.Ctl		
	Z	Χ	Χ	Χ	N/A			DEBOUNCER.CTL		
	Z	X	X	X	N/A			DIFF_DRIVE_ACCEL_LIMIT.CTL		
	<u>Z</u>	X	X	X	N/A			DIFF_DRIVE_KINEMATICS.CTL		
	Z	X	X	X	N/A N/A			DIFF_DRIVE_Kitbot_WheelSize_ENUM.ctl DIFF_DRIVE_Pose_EST.ctl		
	Z	X	X	X	N/A N/A			DIFF_DRIVE_Fose_E31.cti DIFF_DRIVE_ToughBoxMini_GearChoice_ENUM.ctl		
	Z	X	X	X	N/A			DIFF_DRIVE_ToughBoxMini_Gearchoice_ENUM.ctl		
	Z	X	X	X	N/A			DIFF DRIVE TRAIN SIM STATE ENUM.CTL		
	Z	X	X	X	N/A			DIFF DRIVE TRAIN SIM.ctl		
	Ζ	Х	Χ	Χ	NA			DISPLAY_WAYPOINT.ctl		Was UTIL_WAYPOINT.VI
	Ζ	X	X	X	NA			DISPLAY_WEIGHTED_WAYPOINT.ctl		New V1.5. was UTIL_WEIGHTED_WAYPOINIT.VI
	Ζ	Х	Χ	Χ	N/A			ELEV FF.CTL		
	Ζ	Χ	Χ	Χ	N/A			ELEVATOR_SIM.CTL		
	Ζ	Χ	Χ	X	N/A			EXTENDED_KALMAN_CORRECT_FUNC_GROUP.CTL		
	Ζ		Χ	X	N/A			EXTENDED_KALMAN_FILTER.CTL		
	Z	X	Χ	Χ	N/A			FLYWHEEL_SIM.ctl		
	Z	X	X	X	N/A			FUNCTION_GENERATOR.ctl		
	<u>Z</u>	X	X	X	N/A			FUNCTION_GENERATOR_MATRIX.ctl		New 1/26/21
		X	X	X	N/A N/A			HOLONOMIC_DRV_CTRL.CTL TIME INTERPOLATABLE BOOLEAN.CTL		New 1/20/21
	Z	X	\overline{X}	X	N/A N/A			TIME INTERPOLATABLE DOUBLE.CTL		
	Z	X	X		N/A			TIME INTERPOLATABLE POSE2D.CTL		
		X	X	X				TIME INTERPOLATABLE ROTATION2D.CTL		
	Z	X	X	X	N/A			KALMAN FILTER LATENCY COMP FUNC GROUP.CTL		
	Ζ	Χ	Χ	Χ	N/A			KALMAN_FILTER_LATENCY_COMP.CTL		
	Ζ	Χ	Χ	Χ	N/A			KALMAN_FILTER.ctl		
	Ζ	Χ	Χ	Χ				LINEAR_FILTER.CTL		
	Z	X	X	X	N/A			LINEAR_PLANT_INV_FF.ctl		
	Z	X	X	X	N/A			LINEAR_QUADRATIC_REGULATOR.ctl		
	<u>Z</u>	X	X	X				LINEAR_SYSTEM_LOOP.ctl		
		X	X	X	N/A N/A			LINEAR_SYSTEM_SIM.ctl LINEAR SYSTEM.ctl		
		Χ	X	X				LTV DIFF DRIVE CTRL.ctl		
	Z		X	X				LTV DIFF_DRIVE_CTRL.CII LTV DIFF_DRIVE_CTRL STATE_ENUM.ctl		
	Z		X	X				LTV UNICYCLE CONTROLLER.CTL		+
	Z		X	X	N/A			LTV UNICYCLE CONTROLLER INPUT ENUM.ctl		+
	Z		X	X				LTV UNICYCLE CONTROLLER STATE ENUM.ctl		
	Z	Х	X	X				MECA DRIVE KINEMATICS.CTL		
	Z	X	Χ	X				MECA_DRIVE_ODOMETRY.CTL		
	Ζ		Χ	Χ	N/A			MECA_DRIVE_POSE_EST.CTL		
	Ζ	Χ	Χ	Χ				MECA_WHEEL_SPEEDS.CTL		
	Ζ	Χ	Χ	Χ				MEDIAN_FILTER.CTL		
	Ζ	X	Χ	X	N/A			MERWE_SCALED_SIGMA_PTS.ctl		

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Z	X	Χ	Χ	N/A	OBSERVER SNAP LIST ITEM.CTL	
Z	X	Χ	Χ	N/A	OBSERVER SNAPSHOT.CTL	
Z	Χ	Χ	X	N/A	PARAM STACK ITEM.CTL	
Z	X	X	X	N/A	PARAM STACK.CTL	
Z	X	X	X	N/A	PID ADV LIMITS.CTL	
Z	X	X	X	N/A	PID ADV TUNING.CTL	
Z	X	X	X	N/A	PID CONTROLLER.CTL	
Z	X	X	X	N/A	PID_ERROR_TOLERANCE.CTL	
	X	X	X	N/A	PID_ERROR_TOLERANCE.CTL PID_INPUT_LIMITS.CTL	
Z						
Z	X	X	X	N/A	PID_TUNING.CTL	
Z	X	X	X	N/A	POSE2D.CTL	
Z	X	X	X	N/A	POSE3D.CTL	
Z	X	X	X	N/A	POSEwCURVATURE.CTL	
Z	Χ	Χ	X	N/A	PROFILED_PID_CONTROLLER.CTL	
Z	Χ	Χ	X	N/A	QUATERNION.CTL	
Z	Χ	Χ	X	N/A	RAMSETE_EXE_TUNING.CTL	
Z	Χ	Χ	X	N/A	RAMSETE.CTL	
Z	X	Χ	X	N/A	ROTATION2D.CTL	
Z		Χ	X	N/A	ROTATION3D.CTL	
Z	X	Χ	X	N/A	SIMPLE_MOTOR_FF.CTL	
Z	X	Χ	Χ	N/A	SINGLE_JOINT_ARM_SIM.CTL	
Z	X	Χ	Χ	N/A	SLEW RATE LIMITER.CTL	
Z	Χ	Χ	Χ	N/A	SPLINE CTRL VECTOR.CTL	
Z	Χ	Χ	X	N/A	SPLINE.CTL SPLINE.	
Z	Χ	Χ	X	N/A	SWERVE DRIVE KINEMATICS.CTL	
Z	Χ	X	X	N/A	SWERVE DRIVE MODULE STATE.CTL	
Z	X	X	X	N/A	SWERVE DRIVE ODOMETRY.CTL	
Z	X	X	X	N/A	SWERVE DRIVE Pose EST.CTL	
Z	X	X	X	N/A	TIMER.CTL	
Z	X	X	X	N/A	TRAJ CONFIG.CTL	
Z	X	X	X	N/A	TRAJ CONSTRAINT CENTRIPETAL ACCEL.CTL	
Z	X	X		N/A		
			. X	I IWA I		
	X		X		TRAJ_CONSTRAINT_DIIF_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL	
Z	Χ	Χ	X	N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL	Routine exists, it is just a shell
\		X	X	N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL	Routine exists, it is just a shell
۱ Z	Χ	X X X	X	N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL	Routine exists, it is just a shell
\ Z Z	X X	X X X	X	N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL	Routine exists, it is just a shell
Z Z Z Z	X X X	X X X X	X X X X	N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL	Routine exists, it is just a shell
Z	X X X X	X X X X X	X X X X	N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL	Routine exists, it is just a shell
Z	X X X X	X X X X X X	X X X X X	N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL	Routine exists, it is just a shell
Z	X X X X X	X X X X X X X	X X X X X X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL	Routine exists, it is just a shell
Z	X X X X	X X X X X X X	X X X X X X X	N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL	Routine exists, it is just a shell
Z	X X X X X X	X X X X X X X X	X X X X X X X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL	Routine exists, it is just a shell
Z	X X X X X	X X X X X X X X X	X X X X X X X X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z	X X X X X X	X X X X X X X X X	X X X X X X X X X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL	Routine exists, it is just a shell
Z Z Z Z Z Z Z Z Z Z Z Z	X X X X X X X	X X X X X X X X X X X	X X X X X X X X X X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL	Routine exists, it is just a shell
Z	X X X X X X X X	X X X X X X X X X X X X	X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL	Routine exists, it is just a shell
Z	X X X X X X X X	X X X X X X X X X X X X X	X X X X X X X X X X X X X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE_CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY_CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE_CTL	Routine exists, it is just a shell
Z	X X X X X X X X	X X X X X X X X X X X X X X X X X X X	X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE.CTL TWIST2D.CTL	Routine exists, it is just a shell
Z	X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE.CTL TWIST2D.CTL TWIST3D.CTL	Routine exists, it is just a shell
Z	X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TWIST2D.CTL TWIST3D.CTL UNSCENTED_KALMAN_CORRECT_FUNC_GROUP.CTL	Routine exists, it is just a shell
Z	X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJ_STATE.CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRAJ_ECTORY_CTL TRANSFORM_D.CTL TRANSFORM_D.CTL TRANSFORM_D.CTL TRANSLATION_D.CTL TRANSLATION_D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE_STATE.CTL TWIST_D.CTL TWIST_D.CTL TWIST_D.CTL UNSCENTED_KALMAN_CORRECT_FUNC_GROUP.CTL UNSCENTED_KALMAN_FILTER.ctl	Routine exists, it is just a shell
Z	X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY_SPLINE_TYPE_ENUM.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TRAPEZOID_PROFILE_CTL TWIST2D.CTL TWIST2D.CTL TWIST3D.CTL UNSCENTED_KALMAN_CORRECT_FUNC_GROUP.CTL UNSCENTED_KALMAN_NEW_FUNC_GROUP.CTL	Routine exists, it is just a shell
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Z	X X X X X X X X X X X X X X X	X X X X X X X X X X X X X X X X X X X	X	N/A N/A N/A N/A N/A N/A N/A N/A N/A N/A	TRAJ_CONSTRAINT_DIIF_DRIVE_VOLTAGE.CTL TRAJ_CONSTRAINT_JERK.CTL TRAJ_CONSTRAINT_MECA_DRIVE_KINEMATICS.CTL TRAJ_CONSTRAINT_MINMAX.CTL TRAJ_CONSTRAINT_SWERVE_DRIVE_KINEMATICS.CTL TRAJ_STATE.CTL TRAJ_ECTORY_SPLINE_TYPE_ENUM.CTL TRAJECTORY.CTL TRANSFORM2D.CTL TRANSFORM3D.CTL TRANSLATION2D.CTL TRANSLATION3D.CTL TRAPEZOID_PROFILE_CONSTRAINT.CTL TRAPEZOID_PROFILE_STATE.CTL TWIST2D.CTL TWIST2D.CTL UNSCENTED_KALMAN_CORRECT_FUNC_GROUP.CTL UNSCENTED_KALMAN_NEW_FUNC_GROUP.CTL UTIL_PATHFINDER_CONFIG.CTL WAYPOINTS.CTL	Delete – obsolete