#pragma config(Motor, port1, leftBar, tmotorVex393\_HBridge, openLoop)

#pragma config(Motor, port2, frontright, tmotorVex393\_MC29, openLoop, reversed)

#pragma config(Motor, port3, backright, tmotorVex393\_MC29, openLoop, reversed)

#pragma config(Motor, port6, frontleft, tmotorVex393\_MC29, openLoop)

#pragma config(Motor, port7, backleft, tmotorVex393\_MC29, openLoop)

#pragma config(Motor, port10, rightBar, tmotorVex393\_HBridge, openLoop)

//\*!!Code automatically generated by 'ROBOTC' configuration wizard !!\*//

/\*---------------------------------------------------------------------------\*/

/\* \*/

/\* Description: Competition template for VEX EDR \*/

/\* \*/

/\*---------------------------------------------------------------------------\*/

// This code is for the VEX cortex platform

#pragma platform(VEX2)

// Select Download method as "competition"

#pragma competitionControl(Competition)

//Main competition background code...do not modify!

#include "Vex\_Competition\_Includes.c"

/\*---------------------------------------------------------------------------\*/

/\* Pre-Autonomous Functions \*/

/\* \*/

/\* You may want to perform some actions before the competition starts. \*/

/\* Do them in the following function. You must return from this function \*/

/\* or the autonomous and usercontrol tasks will not be started. This \*/

/\* function is only called once after the cortex has been powered on and \*/

/\* not every time that the robot is disabled. \*/

/\*---------------------------------------------------------------------------\*/

void pre\_auton()

{

// Set bStopTasksBetweenModes to false if you want to keep user created tasks

// running between Autonomous and Driver controlled modes. You will need to

// manage all user created tasks if set to false.

bStopTasksBetweenModes = true;

// Set bDisplayCompetitionStatusOnLcd to false if you don't want the LCD

// used by the competition include file, for example, you might want

// to display your team name on the LCD in this function.

// bDisplayCompetitionStatusOnLcd = false;

// All activities that occur before the competition starts

// Example: clearing encoders, setting servo positions, ...

}

/\*---------------------------------------------------------------------------\*/

/\* \*/

/\* Autonomous Task \*/

/\* \*/

/\* This task is used to control your robot during the autonomous phase of \*/

/\* a VEX Competition. \*/

/\* \*/

/\* You must modify the code to add your own robot specific commands here. \*/

/\*---------------------------------------------------------------------------\*/

task autonomous()

{

// ..........................................................................

// Insert user code here.

// ..........................................................................

// Remove this function call once you have "real" code.

AutonomousCodePlaceholderForTesting();

}

/\*---------------------------------------------------------------------------\*/

/\* \*/

/\* User Control Task \*/

/\* \*/

/\* This task is used to control your robot during the user control phase of \*/

/\* a VEX Competition. \*/

/\* \*/

/\* You must modify the code to add your own robot specific commands here. \*/

/\*---------------------------------------------------------------------------\*/

task usercontrol()

{

// User control code here, inside te loop

while (true)

{

//chassis motor control

motor[port2] = vexRT[Ch2];

motor[port3] = vexRT[Ch2];

motor[port6] = vexRT[Ch3];

motor[port7] = vexRT[Ch3];

/\*--------------------------------------------------bar lift--------------------------------------------------\*/

//up

if (vexRT[Btn6U] = 1)

{

motor[port1] = 100;

motor[port10] = 100;

}

//down

else

if (vexRT[Btn6D] = 1)

{

motor[port1] = -100;

motor[port10] = -100;

}

UserControlCodePlaceholderForTesting();

}

}

=====================bar lift test code======================================

#pragma config(Sensor, dgtl1, bump, sensorTouch)

#pragma config(Motor, port2, leftmotor, tmotorVex393\_MC29, openLoop)

#pragma config(Motor, port3, rightmotor, tmotorVex393\_MC29, openLoop)

//\*!!Code automatically generated by 'ROBOTC' configuration wizard !!\*//

task main()

{

while(true)

{

if (SensorValue[bump] == 0)

{

motor[port2] = 60;

motor[port3] = 60;

}

else if (SensorValue[bump] == 1)

{

motor[port2] = 0;

motor[port3] = 0;

}

}

}