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1  /*-----*/
2  /*      5249Z-Ignite      */
3  /*      Version: 1.2.0    */
4  /*      File: RobotConfig.cpp      */
5  /*      Description: Instantiates extern objects in RobotConfig.h */
6  /*-----*/
7  #include "vex.h"
8  #include "RobotConfig.h"
9  using namespace vex;
10 brain Brain;
11
12 //Initializations from RobotConfig.h
13 //Motors
14 motor mtrLeft = motor(PORT12, false);
15 motor mtrRight = motor(PORT19, true);
16 motor mtrLeftFront = motor(PORT11, false);
17 motor mtrRightFront = motor(PORT20, true);
18 motor mtrArm = motor(PORT2, ratio36_1);
19 motor mtrIntakeLeft = motor(PORT1, ratio36_1, true);
20 motor mtrIntakeRight = motor(PORT10, ratio36_1, false);
21 motor mtrRampLift = motor(PORT18, ratio36_1, true);
22
23 //Peripherals
24 light cubeBump = light(Brain.ThreeWirePort.F);
25 limit limArm = limit(Brain.ThreeWirePort.E);
26 limit limRamp = limit(Brain.ThreeWirePort.G);
27 limit limArmBottom = limit(Brain.ThreeWirePort.H);
28 inertial navInert = inertial(PORT13);
29 controller ctrPrimary = controller(controllerType::primary); //Create the controller
30 //gyro gyroDrive = gyro(Brain.ThreeWirePort.H);
31
32 //extern variables
33 bool colorRed;
34 int autonMode;
35
36 void wait(int time){
37     task::sleep(time);
38 }
39

```