Old auto v 1.5 ( a new method for autoPrograming)

Two pid controllers run on the srx

One is the main postion other is the auxillary

* Primary pid (motion magic)
  + Position setpoint
  + Enter inches and then convert it to encoder ticks
  + Needs curise velocity and acceloration
* Auxiliary PID (imu yaw for turning)
* Drive train is assumed to be tank drive
  + one side has master talon
  + other side follows the left side for setpoint
    - I don’t know if this will work but we will see
    - Could use two encoder feedback I think

Helpful notes

Needs a kf

* F-gain = (100% X 1023) / 4123 F-gain = 0.2481
  + Now let’s calculate a Feed-forward gain so that 100% motor output is calculated when the requested speed is 4123 native units per 100ms.