# Changing paths

1. Find the path you want to edit based on the table below.
2. Find the paths file you need to load based on the table below.

|  |  |  |  |
| --- | --- | --- | --- |
| Automode | Description | Paths | PathFile |
| 0 | Start in center, single hatch on cargo ship left | CenterHab2CargoFrontLeft | pathscargo |
| 1 | Start in center, two hatches on cargo ship, second hatch from left loading station | CenterHab2CargoFrontLeft  CargoFrontLeftLSLeft  LSLeftCargoFrontRight | pathscargo  pathsint100  pathsint |
| 2  Not tuned | Start in center, single hatch on cargo ship right | CenterHab2CargoFrontRight | pathscargo |
| 3  Not tuned | Start in center, two hatches on cargo ship, second hatch from right loading station | CenterHab2CargoFrontRight  CargoFrontRightLSRight  LSRightCargoFrontLeft | pathscargo  pathsint100  pathsint |
| 4 | Two on Left Rocket | LeftHABLeftRocket  LeftRocketLSLeft  LSLeftRocketLeft | pathsrocket  pathsint  pathsint |
| 5 | One on Left Rocket | LeftHABLeftRocket | pathsrocket |
| 6 | Two on Right Rocket | RightHABRightRocket  RightRocketLSRight  LSRightRocketRight | pathsrocket  pathsint  pathsint |
| 7 | One on Right Rocket | RightHABRightRocket | pathsrocket |
| 8 | None – use for standstorm mode |  |  |
| 9 | For SW Use only |  |  |

1. Note, edit the paths using the FRC program FRC PathWeaver.
   1. All paths are stored under (gitrepopath)/robots/phaser/src/main/paths
   2. Load a paths file by choosing “Import Project” and navigating to the path directory
2. After changing a path, you must press the “Build Paths” button.
3. After rebuilding a path, you must deploy to the robot using the “WPILib: Deploy Robot Code” command in visual studio code, while connected to the robot.

# Changing parameters

1. Open the parameters file in visual studio code, at (gitrepopath)/robots/phaser/src/main/deploy/phaser.dat.
2. Make the edits and save the file.
3. After changing the file, you must deploy to the robot using the “WPILib: Deploy Robot Code” command in visual studio code, while connected to the robot.