

com._604robotics.utils

Class DualVictor

java.lang.Object
com._604robotics.utils.DualVictor

All Implemented Interfaces:

PIDOutput

```
public class DualVictor
extends Object
implements PIDOutput
```

Control two Victors like they're one. Useful for PID controllers. Also, it's springable (see SpringableVictor).

Constructor Summary

Constructors

| Constructor and Description |
|---|
| DualVictor (int leftPort, int rightPort) Initialize a DualVictor with a left and a right PWM port. |
| DualVictor (int leftSlot, int leftPort, int rightSlot, int rightPort) Initializes a DualVictor with left and right slot and PWM port. |
| DualVictor (Victor leftVictor, Victor rightVictor) Initializes a DualVictor with left and right slot and PWM port. |

Method Summary

Methods

| Modifier and Type | Method and Description |
|-------------------|---|
| double | get () Checks the current power the Victors are set to. |
| boolean | getSprung () Has the victor been sprung? |
| void | pidWrite (double output) Function to hook into the PIDController. |
| void | reload () If the Victor has been sprung, unspring it; if not, set the output to 0. |
| void | set (double speed) Sets the power of the Victors. |
| void | setController (PIDController controller) Sets the PIDController for this DualVictor, if there is one. |
| void | setDeadband (double lowerDeadband, double upperDeadband) Sets the deadband for the DualVictor. |
| void | setLeftInversion (boolean inversion) Sets the inversion for the "left" Victor. |
| void | setRightInversion (boolean inversion) Sets the inversion for the "right" Victor. |
| void | setSafetyEnabled (boolean enabled) Sets whether or not safety is enabled. |
| void | spring () Springs the victor. |

Methods inherited from class java.lang.Object

clone, equals, finalize, getClass, hashCode, notify, notifyAll, toString, wait, wait, wait

Constructor Detail

DualVictor

```
public DualVictor(int leftPort,
                  int rightPort)
```

Initialize a DualVictor with a left and a right PWM port.

Parameters:

- leftPort - The PWM port of the "left" Victor.
- rightPort - The PWM port of the "right" Victor.

DualVictor

```
public DualVictor(int leftSlot,
                  int leftPort,
                  int rightSlot,
                  int rightPort)
```

Initializes a DualVictor with left and right slot and PWM port.

Parameters:

- leftSlot - The slot the "left" Victor is plugged into.
- leftPort - The PWM port of the "left" Victor.
- rightSlot - The slot the "right" Victor is plugged into.
- rightPort - The PWM port of the "right" Victor.

DualVictor

```
public DualVictor(Victor leftVictor,
                  Victor rightVictor)
```

Initializes a DualVictor with left and right slot and PWM port.

Parameters:

- leftVictor - The "left" Victor.
- rightVictor - The "right" Victor.

Method Detail

getSprung

```
public boolean getSprung()
```

Has the victor been sprung?

Returns:

- Whether or not the victor has been sprung.

spring

```
public void spring()
```

Springs the victor.

setLeftInversion

```
public void setLeftInversion(boolean inversion)
```

Sets the inversion for the "left" Victor.

Parameters:

- inversion - Is it inverted?

setRightInversion

```
public void setRightInversion(boolean inversion)
```

Sets the inversion for the "right" Victor.

Parameters:

`inversion` - Is it inverted?

get

```
public double get()
```

Checks the current power the Victors are set to.

Returns:

The current power the Victors are set to.

set

```
public void set(double speed)
```

Sets the power of the Victors.

Parameters:

`speed` - The speed to set.

pidWrite

```
public void pidWrite(double output)
```

Function to hook into the PIDController. Sets the power of the Victors.

Specified by:

`pidWrite` in interface `PIDOutput`

Parameters:

`output` - The speed to set.

setDeadband

```
public void setDeadband(double lowerDeadband,  
                        double upperDeadband)
```

Sets the deadband for the DualVictor. The default is no deadband.

Parameters:

`lowerDeadband` - The lower bound of the deadband.

`upperDeadband` - The upper bound of the deadband.

setSafetyEnabled

```
public void setSafetyEnabled(boolean enabled)
```

Sets whether or not safety is enabled.

Parameters:

`enabled` - Whether or not safety is enabled.

reload

```
public void reload()
```

If the Victor has been sprung, unsprung it; if not, set the output to 0.

setController

```
public void setController(PIDController controller)
```

Sets the PIDController for this DualVictor, if there is one. If the PIDController is enabled, reload will assume it's updating it, and won't reset the output to 0.

Parameters:

controller - The PIDController for this DualVictor.

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Summary: Nested | Field | Constr | Method Detail: Field | Constr | Method