

com._604robotics.robot2012.machine

Class TurretMachine

java.lang.Object
com._604robotics.robot2012.machine.TurretMachine

All Implemented Interfaces:

StrangeMachine

```
public class TurretMachine
extends Object
implements StrangeMachine
```

Machine to control the turret.

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Nested Class Summary

Nested Classes

Modifier and Type	Class and Description
static interface	TurretMachine.TurretState The possible states the turret could be in.

Constructor Summary

Constructors

Constructor and Description
TurretMachine (PIDController controller, RotationProvider provider, Encoder encoder) Initializes a new TurretMachine.

Method Summary

Methods

Modifier and Type	Method and Description
boolean	crank (int state) Causes the Machine to strive for the target state.
void	setTurretSidewaysPosition (double turretSidewaysPosition) Sets the position to use as "SIDEWAYS".
boolean	test (int state) Tests if the Machine has yet attained the target state.

Methods inherited from class java.lang.Object

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

Constructor Detail

TurretMachine

```
public TurretMachine(PIDController controller,
                    RotationProvider provider,
                    Encoder encoder)
```

Initializes a new TurretMachine.

Parameters:

controller - The `PIDController` to control.

provider - The `RotationProvider` to draw aiming data from.

encoder - The encoder measuring the horizontal position of the turret.

Method Detail

test

```
public boolean test(int state)
```

Description copied from interface: [StrangeMachine](#)
Tests if the Machine has yet attained the target state.

Specified by:

`test` in interface [StrangeMachine](#)

Parameters:

`state` - The target state.

Returns:

Whether or not the Machine has attained the target state.

crank

```
public boolean crank(int state)
```

Description copied from interface: [StrangeMachine](#)
Causes the Machine to strive for the target state.

Specified by:

`crank` in interface [StrangeMachine](#)

Parameters:

`state` - The state to strive for.

Returns:

Whether or not the target state has been reached.

setTurretSidewaysPosition

```
public void setTurretSidewaysPosition(double turretSidewaysPosition)
```

Sets the position to use as "SIDEWAYS".

Parameters:

`turretSidewaysPosition` - The position to use as "SIDEWAYS", in degrees.

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