com._604robotics.robot2012.autonomous

Class PIDDriveEncoderOutput

java.lang.Object
  com._604robotics.robot2012.autonomous.PIDDriveEncoderOutput

All Implemented Interfaces:

PIDOutput

```
public class PIDDriveEncoderOutput
extends Object
implements PIDOutput
```

This class implements the default PIDOutput class provided in the WPILib API. The class determines motor power to the robot drive so that the robot will drive backwards, depending on the encoder values.

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Constructor Summary

Constructors

Constructor and Description
PIDDriveEncoderOutput(RobotDrive driveTrain) Initializes a new PIDDriveEncoderOutput.
PIDDriveEncoderOutput(RobotDrive driveTrain, boolean inversion) Initializes a new PIDDriveEncoderOutput.

Method Summary

Methods

Modifier and Type	Method and Description
void	**pidWrite**(double output) Robot will drive with the configured power, and swerve determined by the encoder readings.

Methods inherited from class java.lang.Object

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

Constructor Detail

PIDDriveEncoderOutput

```
public PIDDriveEncoderOutput(RobotDrive driveTrain,
                             boolean inversion)
```

Initializes a new PIDDriveEncoderOutput.

Parameters:

driveTrain - The RobotDrive object to control.

inversion - Should the output be inverted?

PIDDriveEncoderOutput

```
public PIDDriveEncoderOutput(RobotDrive driveTrain)
```

Initializes a new PIDDriveEncoderOutput.

Parameters:

driveTrain - The RobotDrive object to control.

Method Detail

pidWrite

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

Robot will drive with the configured power, and swerve determined by the encoder readings.

Specified by:

`pidWrite` in interface `PIDOutput`

Parameters:

`output` - The output of the PID controller.