

com.\_604robotics.robot2012.machine

## Class ElevatorMachine

java.lang.Object  
com.\_604robotics.robot2012.machine.ElevatorMachine

All Implemented Interfaces:

StrangeMachine

```
public class ElevatorMachine
extends Object
implements StrangeMachine
```

Machine to control the elevator.

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### Nested Class Summary

Nested Classes

Modifier and Type	Class and Description
static interface	<a href="#">ElevatorMachine.ElevatorState</a> Various possible states the elevator can be in.

### Constructor Summary

Constructors

Constructor and Description
<a href="#">ElevatorMachine</a> ( <a href="#">PIDController</a> controller, <a href="#">Encoder</a> encoder) Initializes a new ElevatorMachine.

### Method Summary

Methods

Modifier and Type	Method and Description
boolean	<a href="#">crank</a> (int state) Causes the Machine to strive for the target state.
boolean	<a href="#">test</a> (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

#### ElevatorMachine

```
public ElevatorMachine(PIDController controller,
                       Encoder encoder)
```

Initializes a new ElevatorMachine.

Parameters:

- `controller` - A PIDController to control.
- `encoder` - The encoder monitoring the elevator's vertical position.

## 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.

[Overview](#) [Package](#) **[Class](#)** [Tree](#) [Deprecated](#) [Index](#) [Help](#)

[Prev Class](#) **[Next Class](#)** [Frames](#) [No Frames](#) [All Classes](#)

[Summary: Nested](#) | [Field](#) | [Constr](#) | [Method](#) [Detail: Field](#) | [Constr](#) | [Method](#)