2022-03-12 (Sat)

Lift Self-Correcting logic to prevent the Lift arms from slowly creeping upward during the match.

In ClimberSubsystem constructor

    Reset Climber encoders on Falcon motors. (talonFX.encoder.reset)

    Initialize self-Correction variables (init values)

        minValue = 0

        maxValue = 14900

        safetyOffset = 3506

        midValue = (maxEncoder + minEncoder)/2 (value=7450)

        selfCorrection = true // self-correction flag

In Robot.teleOpInit

    Go back to init Values

While Robot is running (teleOp mode)

    In Climber subsystem

    If (**selfCorrection**==true)

    get **encoderValue** using `talonFX.getSensorCollection.getIntegratedSensorAbsolutePosition`

    When **encoderValue** is > (**maxValue** - **safetyOffset**)

        Lower Arm to **midValue**

    If climberButtonPressed Then disable SelfCorrection

        selfCorrection = false

Disable SelfCorrection (override) by pressing **Start** button (to start using the Lift manually)

Re-Enable SelfCorrection by pressing **Back** button (re-enable SelfCorrection, stop using the Lift manually)