

2022-03-10

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

In `Robot.autonomousInit`

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

Initialize self-Correction variables (init values)

minEncoder to `talonFX.getAbsEncoder` value + some **safetyOffset** at startup

midValue = (**maxEncoder** + **minEncoder**)/2

maxValue = Constant (determined at test/build time)

safetyOffset = Constant (determined at test/build time)

selfCorrection = true // self-correction flag

In `Robot.teleOpInit`

Go back to init Values

If (`selfCorrection == true`)

selfCorrection = false

Check encoder value

When `encoderValue` is > **maxValue**

Lower to `midValue`

If `climberButtonPressed` Then disable `SelfCorrection`

selfCorrection = false