**Functions universal\_variables.h**

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| **Syntax** | void sensorPortAsString(int port) |
| **Purpose** | Convert the port number to a string and print to debug stream |
| **Entry Conditions** | * *port* - the port to be returned as a string |
| **Code**  **Example** | //print "port1" to the debug stream  sensorPortAsString(port1); |

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| **Syntax** | void MotorPortAsString(int port) |
| **Purpose** | Convert the port number to a string and print to debug stream |
| **Entry Conditions** | * *port* - the port to be returned as a string |
| **Code**  **Example** | //print "in1" to the debug stream  sensorPortAsString(in1); |

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| **Syntax** | void assignXDriveMotorTrim(float value) |
| **Purpose** | Assign a value for the X-drive motor trim. Needed only if robot has x-drive. |
| **Entry Conditions** | * *value* - the desired motor trim value |
| **Code**  **Example** | //assign x-drive motor trim value  assignXDRiveMotorTrim(1.2); |

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| **Syntax** | void assignLiftMotorTrim(float value) |
| **Purpose** | Assign a value for the lift motor trim |
| **Entry Conditions** | * *value* - the desired motor trim value |
| **Code**  **Example** | //assign lift motor trim value  assignLiftMotorTrim(0.7); |

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| **Syntax** | void assignTurnMotorTrim(float value) |
| **Purpose** | Assign a value for the turn motor trim |
| **Entry Conditions** | * *value* - the desired motor trim value |
| **Code**  **Example** | //assign turn motor trim value  assignTurnMotorTrim(0.7); |

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| **Syntax** | void namePositions(string positionA, string positionB) |
| **Purpose** | rename the autonomous starting positions |
| **Entry Conditions** | * *positionA* - the new name assigned to position1 * *positionB* - the new name assigned to positoin2 |
| **Code**  **Example** | //create new position names  string one = “one”;  string two = “two”;  //name the positions  namePositions(one, two); |