The parameters (green cells in file) to configure are…

 **Vprog**: This is the maximum target velocity in rotations per second. (Note if your desired max speed is in RPM, you must multiply by 60).

 **Dist**: The final target position to servo to in rotations.

 **T1** and **T2**: This are the acceleration time constants. By tweaking T1, you can control how much of a ramp-up there is until reaching the peak velocity. By tweaking T2, you can control how much rounding there is during the transition between the ramp and the peak velocity. Watch the blue velocity curve and observe how it changes a T1 and T2 are modified.

 **Itp**: The duration of each trajectory point. Default is 10ms per point. This effectively determines how resolute each trajectory point is. Regardless of this value however, the Talon will perform the motion profile inner loop every 1ms.

When the curve seems reasonable, the generated trajectory points are serialized a number of ways.

TIP: if this profile is for drivetrain and you know what the max acceleration is before wheel-slip, you can tweak T1 and T2 until the values under the acceleration column are below your max acceleration.