#include <kipr/wombat.h>

//Slicer port 3

//arm port 0

//alignment port 1

int slicer\_open = 2035;

int arm\_down = 1800;

int slicer\_close = 1300;

int arm\_up = 1000;

int main()

{

printf("Get rings\n");

enable\_servos();

//open slicer

set\_servo\_position(3,slicer\_open);

msleep(500);

//lower arm

set\_servo\_position(0,arm\_down);

msleep(500);

//drive forward to ring stand

clear\_motor\_position\_counter(0);

while(get\_motor\_position\_counter(0) < 400)

{

motor(0,20);

motor(3,20);

}

ao();

//close slicer

set\_servo\_position(3,slicer\_close);

msleep(500);

//raise arm

set\_servo\_position(0,arm\_up);

msleep(500);

//back-up to ring stand

clear\_motor\_position\_counter(0);

while(get\_motor\_position\_counter(0) > -8000)

{

motor(0,-20);

motor(3,-20);

}

ao();

//lower arm onto verticle post

set\_servo\_position(0,arm\_down);

msleep(500);

disable\_servos();

return 0;

}