

```

        liftSeek = 0;
    }
    else {
        // Otherwise, move up
        liftSeek = liftLow;
    }
}
// Remember that we've just toggled
lastLow = 1;
}
else {
    // We haven't just toggled
    lastLow = 0;
}

// If we want to seek
if (liftSeek >= 0) {
    // Run lift motors at power proportional to distance to go
    liftSpeed = -(liftPosition - liftSeek)*liftSeekRate;
}

// Manual Overrides
// Manual up
if (vexRT[Btn7R]) {
    // Set speed and clear flags
    liftSpeed = 127;
    liftSeek = -1;
}
// Manual down
if (vexRT[Btn7D]) {
    // Set speed and clear flags
    liftSpeed = -127;
    liftSeek = -1;
}

// Set Motors
motor[liftR] = liftSpeed;

// Pause to let other tasks run
wait1Msec(10);
}
}

```