#pragma config(Motor, port2, backLeft, tmotorServoContinuousRotation, openLoop)

#pragma config(Motor, port3, backRight, tmotorServoContinuousRotation, openLoop, reversed)

#pragma config(Motor, port4, frontLeft, tmotorServoContinuousRotation, openLoop)

#pragma config(Motor, port5, frontRight, tmotorServoContinuousRotation, openLoop, reversed)

#pragma config(Motor, port6, Servo, tmotorServoStandard, openLoop)

//\*!!Code automatically generated by 'ROBOTC' configuration wizard !!\*//

/\*----------------------------------------------------------------------------------------------------\*\

|\* - Dual Joystick Control with 4 Motors - \*|

|\* ROBOTC on VEX 2.0 Cortex \*|

|\* \*|

|\* This program uses both the Left and the Right joysticks to run the robot using "tank control". \*|

|\* \*|

|\* ROBOT CONFIGURATION \*|

|\* NOTES: \*|

|\* 1) Reversing both right-side motors (ports 2 and 3) in the "Motors and Sensors Setup" is \*|

|\* needed with the "VEX Tumbler" model, but may not be needed for all robot configurations. \*|

|\* 2) Ch1 is the X axis and Ch2 is the Y axis for the RIGHT joystick. \*|

|\* 3) Ch3 is the Y axis and Ch4 is the X axis for the LEFT joystick. \*|

|\* \*|

|\* MOTORS & SENSORS: \*|

|\* [I/O Port] [Name] [Type] [Description] \*|

|\* Motor Port 2 frontRightMotor VEX 3-wire module Right side motor \*|

|\* Motor Port 3 backRightMotor VEX 3-wire module Right side motor \*|

|\* Motor Port 4 frontLefttMotor VEX 3-wire module Left side motor \*|

|\* Motor Port 5 backLeftMotor VEX 3-wire module Left side motor \*|

\\*----------------------------------------------------------------------------------------------------\*/

//+++++++++++++++++++++++++++++++++++++++++++++| MAIN |+++++++++++++++++++++++++++++++++++++++++++++++

void driveRobot()

{

 while(1 == 1)

 {

 //Right side of the robot is controlled by the right joystick, Y-axis

 motor[frontRight] = vexRT[Ch2];

 motor[backRight] = vexRT[Ch2];

 //Left side of the robot is controlled by the left joystick, Y-axis

 motor[backLeft] = vexRT[Ch3];

 motor[frontLeft] = vexRT[Ch3];

 }

}

void launchCatapult()

{

 repeat(forever)

 {

 if(vexRT[Btn6D] == 1)

 {

 setServo(port6, 75);

 }

 else if(vexRT[Btn5D] == 1)

 {

 setServo(port6, 0);

 }

 }

}

task main()

{

 driveRobot();

 launchCatapult();

}

//++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++++