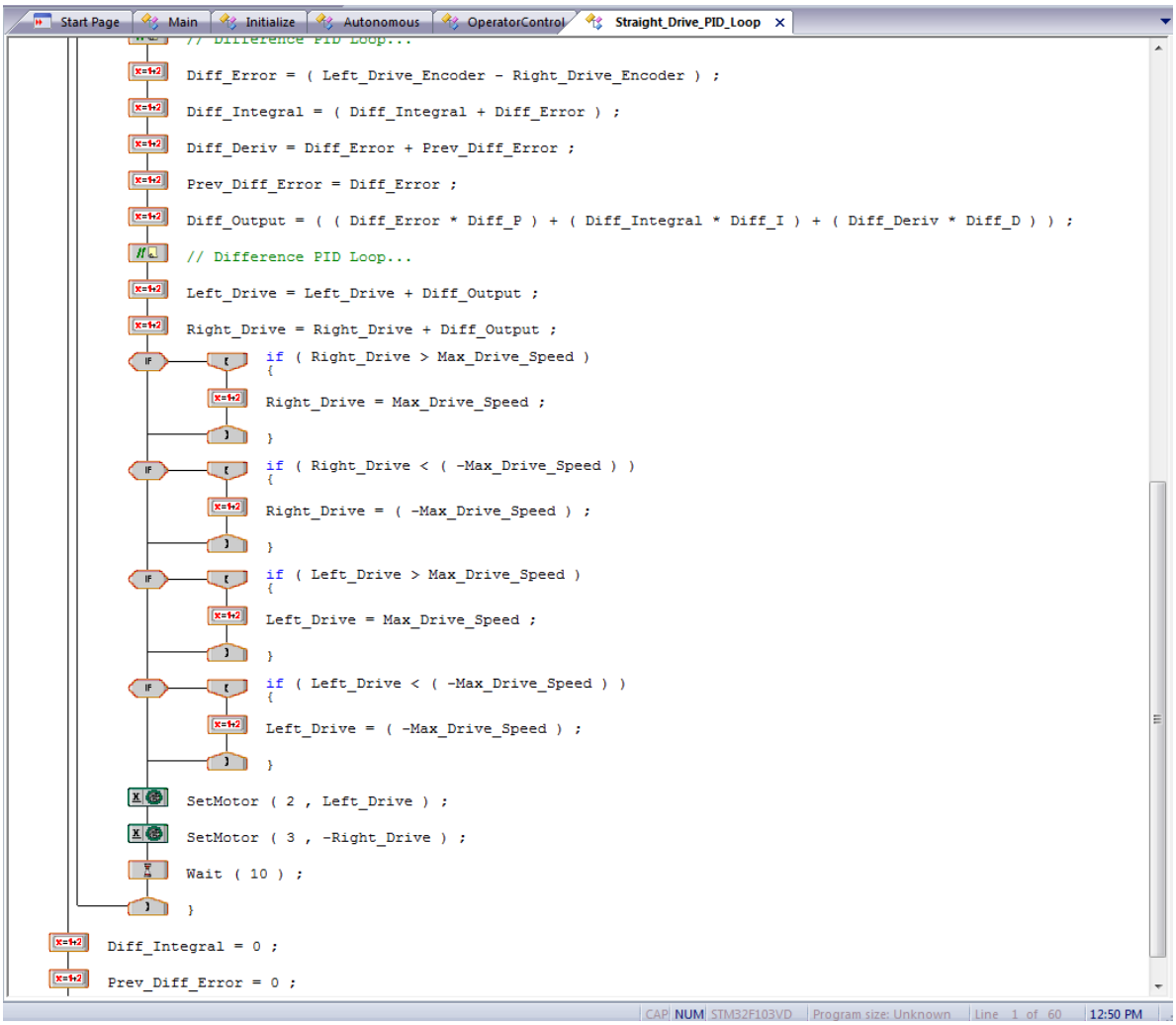
Start Page
Main
Initialize
Autonomous
OperatorControl
Straight_Drive_PID_Loop
// Difference PID Loop...
Diff_Error = (Left_Drive_Encoder - Right_Drive_Encoder) ;
Diff_Integral = (Diff_Integral + Diff_Error) ;
Diff_Deriv = Diff_Error + Prev_Diff_Error ;
Prev_Diff_Error = Diff_Error ;
Diff_Output = ((Diff_Error * Diff_P) + (Diff_Integral * Diff_I) + (Diff_Deriv * Diff_D)) ;
// Difference PID Loop...
Left_Drive = Left_Drive + Diff_Output ;
Right_Drive = Right_Drive + Diff_Output ;
if (Right_Drive > Max_Drive_Speed)
{
Right_Drive = Max_Drive_Speed ;
}
if (Right_Drive < (-Max_Drive_Speed))
{
Right_Drive = (-Max_Drive_Speed) ;
}
if (Left_Drive > Max_Drive_Speed)
{
Left_Drive = Max_Drive_Speed ;
}
if (Left_Drive < (-Max_Drive_Speed))
{
Left_Drive = (-Max_Drive_Speed) ;
}
SetMotor (2 , Left_Drive) ;
SetMotor (3 , -Right_Drive) ;
Wait (10) ;
}
Diff_Integral = 0 ;
Prev_Diff_Error = 0 ;
CAP NUM STM32F103VD Program size: Unknown Line 1 of 60 12:50 PM