

```

#include "Main.h"
void P_Lift ( void )
{
    StartQuadEncoder ( 1 , 2 , 0 );
    StartQuadEncoder ( 3 , 4 , 0 );
    PresetQuadEncoder ( 1 , 2 , 50 );
    PresetQuadEncoder ( 3 , 4 , 50 );
    while ( 1 )
    {
        up = GetJoystickDigital ( 1 , 5 , 2 );
        down = GetJoystickDigital ( 1 , 5 , 1 );
        leftencoder = GetQuadEncoder ( 1 , 2 );
        rightencoder = GetQuadEncoder ( 3 , 4 );
        if ( up == 1 )
        {
            coeff = .25 * ( rightencoder - leftencoder );
            Correction = Abs ( coeff );
            if ( coeff > 0 ) // Left Side Lower
            {
                SetMotor ( 1 , 110 + Correction );
                SetMotor ( 2 , 110 - Correction );
            }
            else if ( coeff < 0 ) // Right Side Lower
            {
                SetMotor ( 1 , 110 - Correction );
                SetMotor ( 2 , 110 + Correction );
            }
            else
            {
                SetMotor ( 1 , 127 );
                SetMotor ( 2 , 127 );
            }
        }
        else if ( down == 1 )
        {
            if ( coeff > 0 ) // left side lower
            {
                SetMotor ( 1 , -110 - Correction );
                SetMotor ( 2 , -110 + Correction );
            }
            else if ( coeff < 0 ) // right side too fast
            {
                SetMotor ( 1 , -110 + Correction );
                SetMotor ( 2 , -110 - Correction );
            }
            else
            {
                SetMotor ( 1 , -127 );
                SetMotor ( 2 , -127 );
            }
        }
        else
        {
            SetMotor ( 1 , 0 );
            SetMotor ( 2 , 0 );
        }
    }
}

```

```

    }
    PrintToScreen ( "Coeff%d\n" , coeff );
    PrintToScreen ( "correct%d\n" , Correction );
    PrintToScreen ( "leftencoder%d\n" , leftencoder );
    PrintToScreen ( "rightencoder%d\n" , rightencoder );
    Wait ( 10 );
}
}

```