#pragma config(Motor, port1, motor, tmotorVex269\_HBridge, openLoop)

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

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

/\* \*/

/\* Description: Competition template for VEX EDR \*/

/\* \*/

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

// This code is for the VEX cortex platform

#pragma platform(VEX2)

// Select Download method as "competition"

#pragma competitionControl(Competition)

//Main competition background code...do not modify!

#include "Vex\_Competition\_Includes.c"

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

/\* Pre-Autonomous Functions \*/

/\* \*/

/\* You may want to perform some actions before the competition starts. \*/

/\* Do them in the following function. You must return from this function \*/

/\* or the autonomous and usercontrol tasks will not be started. This \*/

/\* function is only called once after the cortex has been powered on and \*/

/\* not every time that the robot is disabled. \*/

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

void pre\_auton()

{

// Set bStopTasksBetweenModes to false if you want to keep user created tasks

// running between Autonomous and Driver controlled modes. You will need to

// manage all user created tasks if set to false.

bStopTasksBetweenModes = true;

int lcdScreenMin = 1;

int lcdScreen = 1;

int lcdScreenMax = 3;

bLCDBacklight = true;

const short leftButton = 1;

const short centerButton = 2;

const short rightButton = 4;

while(vrDisabled == 1)

{

if(nLCDButtons == leftButton)

{

if(lcdScreenMin == lcdScreen)

{

lcdScreen = lcdScreenMax;

wait1Msec(250);

}

else

{

lcdScreen--;

wait1Msec(250);

}

}

if(nLCDButtons == rightButton)

{

if(lcdScreenMax == lcdScreen)

{

lcdScreen = lcdScreenMin;

wait1Msec(250);

}

else

{

lcdScreen++;

wait1Msec(250);

}

}

else if(nLCDButtons == leftButton)

{

if(lcdScreenMax == lcdScreen)

{

lcdScreen = lcdScreenMax;

wait1Msec(250);

}

else

{

lcdScreen--;

wait1Msec(250);

}

}

if(lcdScreen == 1 && Program != 1)

{

displayLCDCenteredString(0, "program");

displayLCDCenteredString(1, "1");

if(nLCDButtons == centerButton)

{

Program = lcdScreen;

displayLCDCenteredString(0, "autonomous has");

displayLCDCenteredString(1, "been selected");

wait1Msec(1500);

}

}

else if(lcdScreen == 1 && Program == 1)

{

displayLCDCenteredString(0, "program");

displayLCDCenteredString(1, "[1]");

}

else if(lcdScreen == 2 && Program !=2)

{

displayLCDCenteredString(0, "program");

displayLCDCenteredString(1, "2");

if(nLCDButtons == centerButton)

{

Program = lcdScreen;

displayLCDCenteredString(0, "autonomous has");

displayLCDCenteredString(1, "been selected");

wait1Msec(1500);

}

}

else if(lcdScreen == 2 && Program == 2)

{

displayLCDCenteredString(0, "program");

displayLCDCenteredString(1, "[2]");

}

else if(lcdScreen == 3 && Program !=3)

{

displayLCDCenteredString(0, "program");

displayLCDCenteredString(1, "3");

if(nLCDButtons == centerButton)

{

Program = lcdScreen;

displayLCDCenteredString(0, "autonomous has");

displayLCDCenteredString(1, "been selected");

wait1Msec(1500);

}

}

else if(lcdScreen == 3 && Program == 3)

{

displayLCDCenteredString(0, "program");

displayLCDCenteredString(1, "[3]");

}

}

// Set bDisplayCompetitionStatusOnLcd to false if you don't want the LCD

// used by the competition include file, for example, you might want

// to display your team name on the LCD in this function.

// bDisplayCompetitionStatusOnLcd = false;

// All activities that occur before the competition starts

// Example: clearing encoders, setting servo positions, ...

}

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

/\* \*/

/\* Autonomous Task \*/

/\* \*/

/\* This task is used to control your robot during the autonomous phase of \*/

/\* a VEX Competition. \*/

/\* \*/

/\* You must modify the code to add your own robot specific commands here. \*/

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

task autonomous()

{

// ..........................................................................

if(Program == 1)

{

motor[port1] = 50;

wait(2);

motor[port1] = 0;

}

else if(Program == 2)

{

motor[port1] = 60;

wait(4);

motor[port1] = 0;

}

else if(Program == 3)

{

motor[port1] = 70;

wait(6);

motor[port1] = 0;

}

// ..........................................................................

// Remove this function call once you have "real" code.

AutonomousCodePlaceholderForTesting();

}

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

/\* \*/

/\* User Control Task \*/

/\* \*/

/\* This task is used to control your robot during the user control phase of \*/

/\* a VEX Competition. \*/

/\* \*/

/\* You must modify the code to add your own robot specific commands here. \*/

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

task usercontrol()

{

// User control code here, inside the loop

while (true)

{

// This is the main execution loop for the user control program.

// Each time through the loop your program should update motor + servo

// values based on feedback from the joysticks.

// ........................................................................

// Insert user code here. This is where you use the joystick values to

// update your motors, etc.

// ........................................................................

// Remove this function call once you have "real" code.

UserControlCodePlaceholderForTesting();

}

}