

```

[BEGIN] void P_Lift ( void )
[Variables]

[StartQuadEncoder] StartQuadEncoder ( 1 , 2 , 0 ) ;
[StartQuadEncoder] StartQuadEncoder ( 3 , 4 , 0 ) ;
[PresetQuadEncoder] PresetQuadEncoder ( 1 , 2 , 50 ) ;
[PresetQuadEncoder] PresetQuadEncoder ( 3 , 4 , 50 ) ;

[WHILE] t while ( 1 )
{
    [DigitalIn] up = GetJoystickDigital ( 1 , 5 , 2 ) ;
    [DigitalIn] down = GetJoystickDigital ( 1 , 5 , 1 ) ;
    [AnalogIn] leftencoder = GetQuadEncoder ( 1 , 2 ) ;
    [AnalogIn] rightencoder = GetQuadEncoder ( 3 , 4 ) ;

    [If] t if ( up == 1 )
    {
        [SetVar] coeff = .25 * ( rightencoder - leftencoder ) ;
        [Abs] Correction = Abs ( coeff ) ;

        [If] t if ( coeff > 0 ) // Left Side Lower
        {
            [SetMotor] SetMotor ( 1 , 110 + Correction ) ;
            [SetMotor] SetMotor ( 2 , 110 - Correction ) ;
        }
        [ElseIf] t else if ( coeff < 0 ) // Right Side Lower
        {
            [SetMotor] SetMotor ( 1 , 110 - Correction ) ;
            [SetMotor] SetMotor ( 2 , 110 + Correction ) ;
        }
        [Else] t else
        {
            [SetMotor] SetMotor ( 1 , 127 ) ;
            [SetMotor] SetMotor ( 2 , 127 ) ;
        }
    }
    [ElseIf] t 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 ) ;
}
```