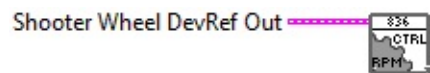


Shooter_Wheel.lvlib:Shooter_Wheel_Control.vi

Help by FRC Team 836 - The RoboBees

This VI provides control of a shooter wheel by using the tbh (Take Back Half) control VI with user

control inputs.



Shooter Wheel DevRef Out

Shooter Config reference



Shooter Data

MotorControlDevRef

DeviceStatus

statuscode

  0

source



Type

 PWM

Invert

☐ OFF/ON

CAN

Device Number

 0

Control Mode

Percent VBus

Semaphore



Max Vout

 0

TalonSRX Control Mode

Percent VBus

PWM

PWM Channel

 PWM 0

DeadBand



Name



maxPositivePwm

 0

minPositivePwm

 0

centerPwm

 0

maxNegativePwm

 0

minNegativePwm

 0

angularRange

 0

CounterDevRef in

DevStatus

statuscode

  0

source



CntIndex

 Ctr 0

RPM Desired



RPM Actual



Shooter Wheel DevRef Out

Shooter Config reference

Shooter Data

MotorControlDevRef

DeviceStatus

status

status is TRUE (X) if an error occurred or FALSE (checkmark) to indicate a warning or that no error occurred.



Right-click the **error in** control on the front panel and select **Explain Error** or **Explain Warning** from the shortcut menu for more information about the error.

code

code is the error or warning code.



Right-click the **error in** control on the front panel and select **Explain Error** or **Explain Warning** from the shortcut menu for more information about the error.

source

source describes the origin of the error or warning.



Right-click the **error in** control on the front panel and select **Explain Error** or **Explain Warning** from the shortcut menu for more information about the error.

 **Type**

 **PWM**

 **PWM Channel**

 **DeadBand**

 **Name**

 **maxPositivePwm**

 **minPositivePwm**

 **centerPwm**

 **maxNegativePwm**

 **minNegativePwm**

 **angularRange**

 **CAN**

 **Device Number**

 **Control Mode**

Semaphore



semaphore is a reference to an existing or newly created semaphore.



Max Vout

TalonSRX Control Mode



Control Mode specifies how the Talon SRX will control the motor. Percent VBus is the standard open-loop mode that is also accessible via the PWM interface on the Talon SRX.



Invert



CounterDevRef in

DevStatus

error in can accept error information wired from VIs previously called. Use this information to decide if any functionality should be bypassed in the event of errors from other VIs.



Right-click the **error in** control on the front panel and select **Explain Error** or **Explain Warning** from the shortcut menu for more information about the error.

status

status is TRUE (X) if an error occurred or FALSE (checkmark) to indicate a warning or that no error occurred.



Right-click the **error in** control on the front panel and select **Explain Error** or **Explain Warning** from the

shortcut menu for more information about the error.

code

code is the error or warning code.



Right-click the **error in** control on the front panel and select **Explain Error** or **Explain Warning** from the shortcut menu for more information about the error.

source

source describes the origin of the error or warning.



Right-click the **error in** control on the front panel and select **Explain Error** or **Explain Warning** from the shortcut menu for more information about the error.

CntIndex

RPM Desired

RPM Actual



C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\WPI\PWM\WPI_PWMDeadband.ctl

Shooter Wheel.lvlib:ShooterControl.ctl



C:\Program Files (x86)\National Instruments\LabVIEW 2015\user.lib\836-Library\Motion Control\Shooter_Wheel\ShooterControl.ctl

WPI_MotorControlDeviceRef.ctl



C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\WPI\MotorControl\WPI_MotorControlDeviceRef.ctl

Shooter Wheel.lvlib:ShooterData.ctl



C:\Program Files (x86)\National Instruments\LabVIEW 2015\user.lib\836-Library\Motion Control\Shooter_Wheel\ShooterData.ctl

FPGA_DIOPWMChannel.ctl



C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\SystemInterfaces\DIO\FPGA_DIOPWMChannel.ctl

WPI_CANJaguar_ControlMode.ctl



C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\WPI\CAN\Jaguar\SubVIs\WPI_CANJaguar_ControlMode.ctl

WPI_MotorControlType.ctl



C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\WPI\MotorControl\WPI_MotorControlType.ctl

Semaphore RefNum



C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Utility\semaphor.llb\Semaphore RefNum

WPI_CANTalonSRX_APIControlMode.ctf



C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\WPI\CAN\TalonSRX\WPI_CANTalonSRX_APIControlMode.ctf

WPI_CounterDevRef.ctf



C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\WPI\Counter\WPI_CounterDevRef.ctf

WPI_MotorControlSetOutput.vi

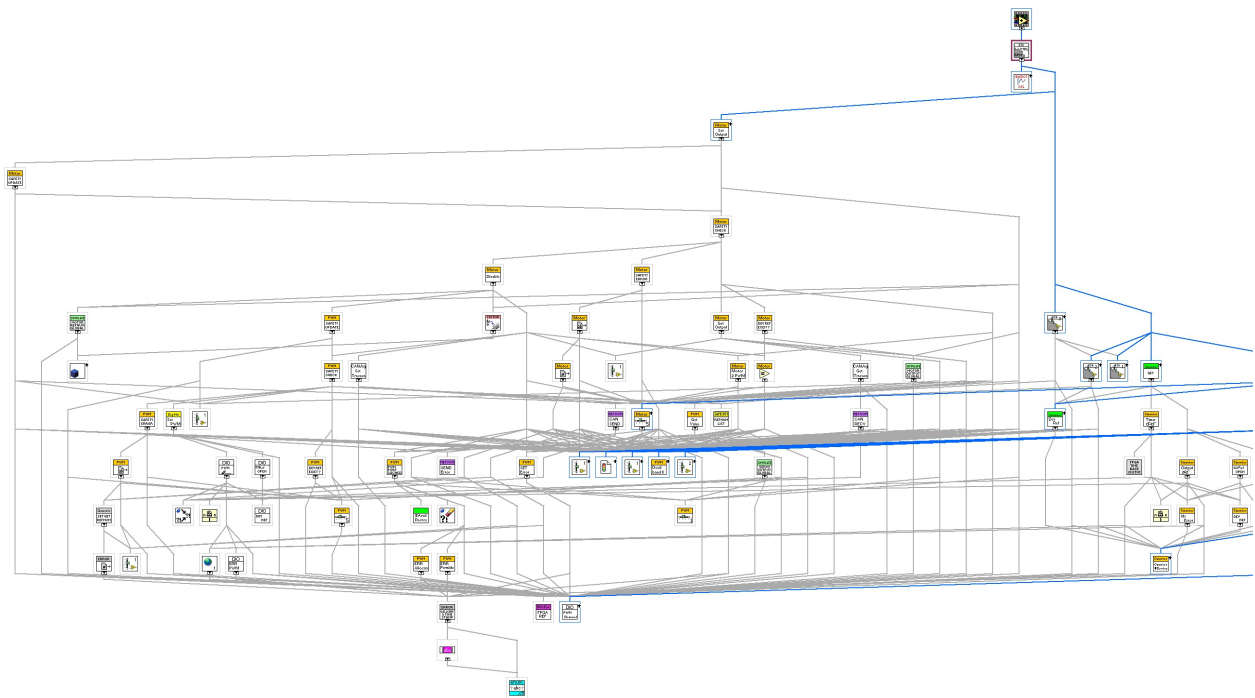


C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\WPI\MotorControl\WPI_MotorControlSetOutput.vi

"Shooter_Wheel.lvlib:Shooter_Wheel_Control.vi History"

Current Revision: 15

Position in Hierarchy



Iconified Cluster Constants