Shooter _Wheel.lvlib:Shooter_Wheel_Get_RPM.vi

Help by FRC Team 836 - The RoboBees

This VI will return the actual revolutions per minute (RPM) of a shooter wheel.
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**

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

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

"Shooter_Wheel.lvlib:Shooter_Wheel_Get_RPM.vi History"

Current Revision: 10

Position in Hierarchy
Iconified Cluster Constants