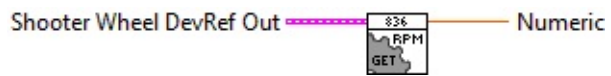


Shooter_Wheel.lvlib:Shooter_Wheel_Get_RPM.vi

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

Numeric

Shooter Config reference



0

Shooter Data

MotorControlDevRef

DeviceStatus

status code
 0

source
[Empty dropdown menu]

Type Invert
PWM 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
[Empty text field]

maxPositivePwm
0

minPositivePwm
0

centerPwm
0

maxNegativePwm
0

minNegativePwm
0

angularRange
0

CounterDevRef in

DevStatus

status code
 0

source
[Empty dropdown menu]

CntIndex
Ctr 0

RPM Desired

[Empty input field]

RPM Actual

[Empty input field]

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.


TF

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.

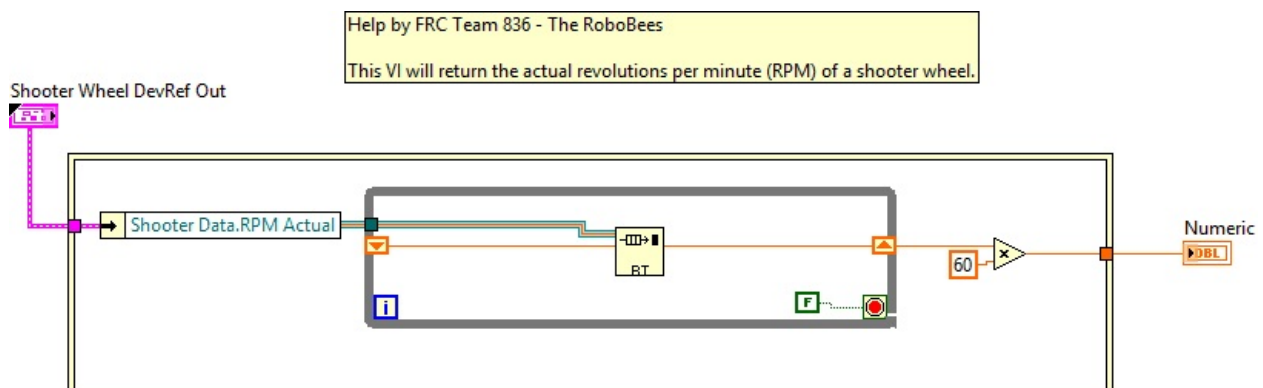
 Right-click the **error in** control on the front panel and select **Explain Error** or **Explain Warning** from the shortcut menu for more information about the error.

CtIndex

RPM Desired

RPM Actual

Numeric



Shooter Wheel.lvlib:ShooterConfig.ctl



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

FPGA_CounterCtrSystemIndex.ctl



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

WPI_PWMDeadband.ctl



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.ctf

WPI_CANJaguar_ControlMode.ctf



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

WPI_MotorControlType.ctf



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

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

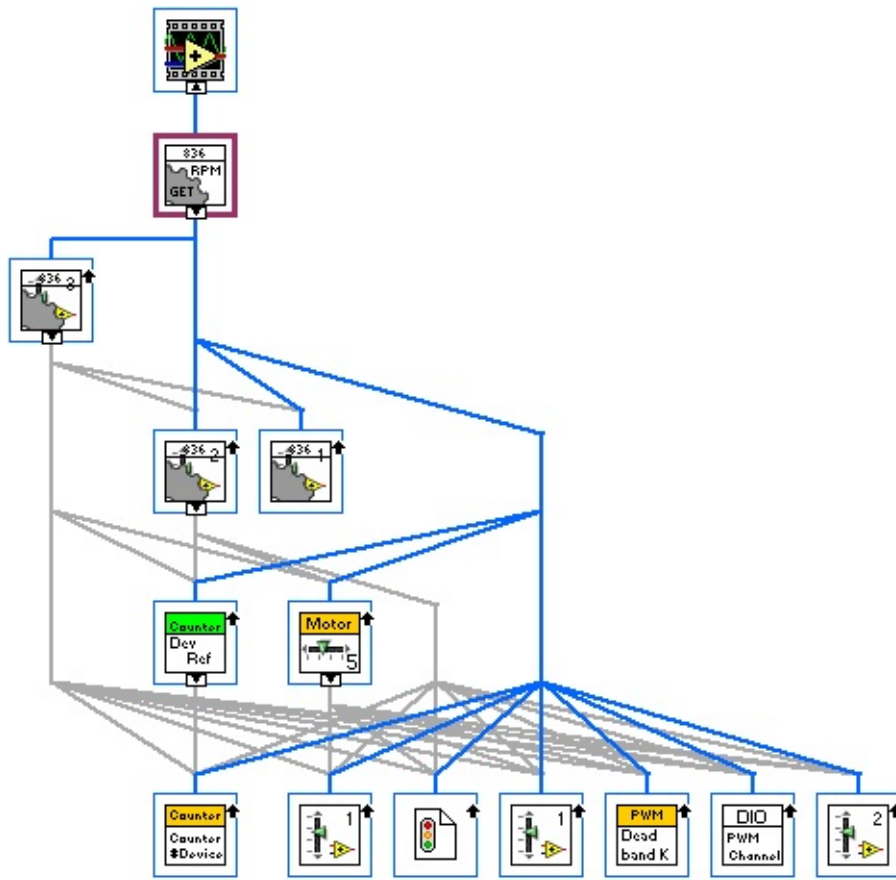


C:\Program Files (x86)\National Instruments\LabVIEW 2015\vi.lib\Rock Robotics\WPI\Counter\WPI_CounterDevRef.ctf

"Shooter_Wheel.lvlib:Shooter_Wheel_Get_RPM.vi History"

Current Revision: 10

Position in Hierarchy



Iconified Cluster Constants