Shooter_Wheel.lvlib:Shooter_Wheel_GetSet.vi

Help by FRC Team 836 - The RoboBees

This VI can either set or get the control parameters of a shooter wheel depending on the users command.
**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 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.

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Error Out

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Shooter Wheel DevRef Out

Shooter Config reference

Shooter Data
status

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PWM

PWM Channel
DeadBand

Name

tab maxPositivePwm

tab minPositivePwm

tab centerPwm

tab maxNegativePwm

tab minNegativePwm

16-bit angularRange

CAN

8-bit Device Number

8-bit Control Mode

Semaphore

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16-bit 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**

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**CntIndex**

**RPM Desired**

**RPM Actual**
Shooter Wheel.lvlib:ShooterConfig.ctl

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

FPGA_CounterCtriSystemIndex.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.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
Position in Hierarchy
Iconified Cluster Constants