#pragma config(Motor, port1, rightMotor, tmotorVex269\_HBridge, openLoop)

#pragma config(Motor, port5, arm, tmotorVex393\_MC29, openLoop)

#pragma config(Motor, port6, claw, tmotorVex269\_MC29, openLoop)

#pragma config(Motor, port10, leftMotor, tmotorVex269\_HBridge, openLoop)

//\*!!Code automatically generated by 'ROBOTC' configuration wizard !!\*//

task main()

{

while(true)

{

// Joystic Control:

motor[port1] = vexRT[Ch2]; //Motor port 1 speed is determined by Ch2 on the VEXnet Transmitter

motor[port10] = vexRT[Ch3]; //Motor port 10 speed is determined by Ch3 on the VEXnet Transmitter

// Button Control:

if(vexRT[Btn5U] == 1) //If button 5U is pressed:

{

motor[port5] = 32; //run motor port 5 at quarter speed (i.e. lift an arm)

}

else if(vexRT[Btn5D] == 1) //If button 5D is pressed:

{

motor[port5] = -32; //run motor port 5 at quarter speed reversed (i.e. lower an arm)

}

else //If neither buttons 5U or 5D are pressed:

{

motor[port5] = 0; //stop motor port 5 (i.e. don't move arm up or down)

}

if(vexRT[Btn6U] == 1) //If button 6U is pressed:

{

motor[port6] = 32; //run motor port 6 at quarter speed (i.e. Open Claw)

}

else if(vexRT[Btn6D] == 1) //If button 6D is pressed:

{

motor[port6] = -32; //run motor port 6 at quarter speed reversed (i.e. lower an arm)

}

else //If neither buttons 6U or 6D are pressed:

{

motor[port6] = 0; //stop motor port 6 (i.e. Close Claw)

}

}

}