

Common Device Classes

Talon SRX	com.ctre.phoenix.motorcontrol.can.WPI_TalonSRX	CTRE (Phoenix V5)
Victor SPX	com.ctre.phoenix.motorcontrol.can.WPI_VictorSPX	CTRE (Phoenix V5)
Talon FX	com.ctre.phoenix6.hardware.TalonFX	CTRE (Phoenix V6)
Pigeon 2	com.ctre.phoenix6.hardware.Pigeon2	CTRE (Phoenix V6)
CAN Coder	com.ctre.phoenix6.hardware.CANCoder	CTRE (Phoenix V6)
Spark MAX	com.revrobotics.CANSparkMax	REV (REVLlib)
Spark Flex	com.revrobotics.CANSparkFlex	REV (REVLlib)
Through-Bore Encoder (RoboRIO, Absolute)	edu.wpi.first.wpilibj.DutyCycleEncoder	WPILib
Through-Bore Encoder (RoboRIO, Relative)	edu.wpi.first.wpilibj.Encoder	WPILib

Motor Basic Control (Talon SRX)

```
private WPI_TalonSRX motor;
@Override
public void robotInit() {
    motor = new WPI_TalonSRX (RobotMap.MOTOR_ID_IDENTIFIER);
    motor.configFactoryDefault(); // factory default
}
@Override
public void teleopInit() {
    motor.set(0.5);
}
@Override
public void teleopPeriodic() {
}
@Override
public void teleopExit() {
    motor.stopMotor();
}
```

Motor Basic Control (Spark MAX)

```
private CANSparkMax motor;
@Override
public void robotInit() {
    motor = new CANSparkMax (RobotMap.MOTOR_IDENTIFIER, CANSparkMaxLowLevelMotorType.kBrushless);
    motor.restoreFactoryDefaults(); // factory default
}
@Override
```



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Motor Basic Control (Spark MAX) (cont)

```
> public void teleopInit() {
    motor.set(0.5);
}
@Override
public void teleopPeriodic() {
}
@Override
public void teleopExit() {
    motor.stopMotor()
}
```

Motor Basic Control (Talon FX)

```
private TalonFX motor;
private DutyCycleOut dutyCycleControl;
private NeutralOut neutralControl;
@Override
public void robotInit() {
    motor = new TalonFX(RobotMap.MOTOR_IDENTIFIER);
    motor.getConfigurator().apply(new TalonFXConfiguration()); // factory default
    dutyCycleControl = new DutyCycleOut(0);
    neutralControl = new NeutralOut();
}
@Override
public void teleopInit() {
    motor.setControl(DutyCycleControl.withOutput(0.5));
}
@Override
public void teleopPeriodic() {
}
@Override
public void teleopExit() {
    motor.setControl(NeutralControl);
}
```

Encoder Access (Talon SRX, SRX Encoder)

```
private static final int PPR = 4096;
private static final double MOTOR_TO_MECHANISM_GEAR_RATIO = 8.0 / 1.0; // driver : driven
private WPI_TalonSRX motor;
@Override
public void robotInit() {
    motor = new WPI_TalonSRX(RobotMap.MOTOR_IDENTIFIER);
    motor.configureFactoryDefault(); // factory default
}
@Override
```



Encoder Access (Talon SRX, SRX Encoder) (cont)

```
> public void teleopPeriodic() {
    double counts = motor.getSelectedSensorPosition();
    double mechanismRotations = counts / PPR / MOTOR_TO_MECHANISM_GEAR_RATIO;
    double countsPer100ms = motor.getSelectedSensorVelocity();
    double mechanismRpm = countsPer100ms / PPR * 600.0 / MOTOR_TO_MECHANISM_GEAR_RATIO;
}
```

Encoder Access (Spark Max, NEO Integrated Encoder)

```
private static final double MOTOR_TO_MECHANISM_GEAR_RATIO = 8.0 / 1.0; // driver : driven
private CANSparkMax motor;
private RelativeEncoder encoder;
@Override
public void robotInit() {
    motor = new CANSparkMax( RobotMap.MOTOR_ID, CANSparkMax.LowLevelMotorType.kBrushless);
    motor.restoreFactoryDefaults(); // factory default
    encoder = motor.getEncoder();
}
@Override
public void teleopPeriodic() {
    double motorRotations = encoder.getPosition();
    double mechanismRotations = motorRotations / MOTOR_TO_MECHANISM_GEAR_RATIO;
    double motorRpm = encoder.getVelocity();
    double mechanismRpm = motorRpm / MOTOR_TO_MECHANISM_GEAR_RATIO;
}
```

Encoder Access (Spark Max, NEO Integrated Encoder)

```
private static final double MOTOR_TO_MECHANISM_GEAR_RATIO = 8.0 / 1.0; // driver : driven
private CANSparkMax motor;
private RelativeEncoder encoder;
@Override
public void robotInit() {
    motor = new CANSparkMax( RobotMap.MOTOR_ID, CANSparkMax.LowLevelMotorType.kBrushless);
    motor.restoreFactoryDefaults(); // factory default
    encoder.setPositionFactor(1 / MOTOR_TO_MECHANISM_GEAR_RATIO);
    encoder.setVelocityFactor(1 / MOTOR_TO_MECHANISM_GEAR_RATIO);
}
@Override
public void teleopPeriodic() {
    double mechanismRotations = encoder.getPosition();
    double mechanismRpm = encoder.getVelocity();
}
```

Encoder Access (Talon FX, Integrated Encoder)

```
private static final double MOTOR_TO_MECHANISM_GEAR_RATIO = 8.0 / 1.0; // driver : driven
private TalonFX motor;
private Status Signal <Do ubl e> positionSignal;
private Status Signal <Do ubl e> velocitySignal;
@Override
public void robotInit() {
    motor = new TalonFX(RobotMap.MOTOR_ID);
    TalonFXConfiguration configuration = new TalonFXConfiguration();
    configuration.FeedbackSource = FeedbackSource.Position;
    configuration.FeedbackRate = 1.0;
    configuration.MotorToMechanismGearRatio = MOTOR_TO_MECHANISM_GEAR_RATIO;
    motor.getConfigurator().apply(configuration);
    positionSignal = motor.getPosition();
    velocitySignal = motor.getVelocity();
}
@Override
public void teleopPeriodic() {
    BaseSystemLogger.getInstance().log("PositionSignal", positionSignal); // only once per 20ms
    BaseSystemLogger.getInstance().log("VelocitySignal", velocitySignal); // only once per 20ms
    double mechanismRotations = positionSignal.getValue();
    double mechanismRotationsPerSecond = velocitySignal.getValue();
}
```

Encoder Access (CANCoder, Absolute)

```
private CANCoder encoder;
private Status Signal <Do ubl e> absPositionSignal;
@Override
public void robotInit() {
    encoder = new CANCoder(RobotMap.CAN_CODER_ID);
    CANCoderConfiguration configuration = new CANCoderConfiguration();
    configuration.MagnetSensorAbsoluteSensorRange = AbsoluteSensorRange.Unsigned_0To1;
    configuration.EncoderCfIRatio = 1.0;
    absPositionSignal = encoder.getPosition();
}
@Override
public void teleopPeriodic() {
    BaseSystemLogger.getInstance().log("AbsPositionSignal", absPositionSignal); // only once per 20ms loop,
    typically in periodic
    // typically absolute encoders are placed on the shaft after a gearbox, so gearbox ratio handling
    isn't needed here.
    double mechanismRotationsAbs = absPositionSignal.getValue(); // [0, 1] -> [0,
    360]
}
```



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