PathPlanner

Overview and Resources:

PathPlanner is a pathing tool developed by team #3015 and is fairly easy to use because of its intuitive, visual nature.

Here are the docs: https://pathplanner.dev/home.html

This page will show you how to effectively use the tool: https://pathplanner.dev/gui-editing-paths-and-autos.html

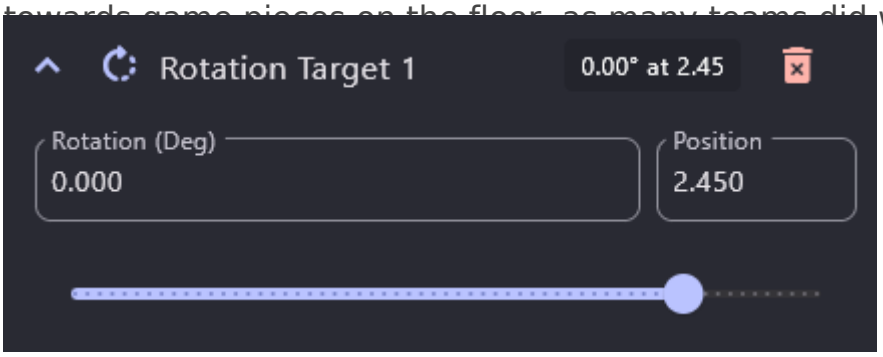
If you have any questions, consult the docs first. They usually contain the answers you desire.

Some of the most important aspects of PathPlanner are:

Rotation Targets:

> Rotation targets define points along the path where the robot should target a given rotation. When path following, the robot will look ahead for the next rotation target, then attempt to rotate to its associated rotation. Rotation targets can be edited in the rotation targets tree. This is only available when holonomic mode is on.

Essentially, this means that you can dictate what direction the robot is facing at any point along the path. This is useful in cases when you want to point your intake towards game pieces on the floor, as many teams did with the notes in 2024.



You can use the *Rotation (Deg)* box to change the heading of the robot and the position slider or the *Position* box to change at what point along the path you want the robot to be at that heading.

Event Markers

> Event markers define points along the path where other commands should be triggered while path following.

This means that you can run commands, such as *intake* or *shoot,* at desired points along the path. Check the docs for further instructions regarding this.

Other Important Aspects to Consider

- Waypoints
- Path Optimization
- Command Groups
- Global Constraints

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