

Group 5

Matthew robot

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How to run:

Build and source ros2

```
ros2 run group5joy joySub
```

Mapping:

Created a node that subscribes to 'joy' and publishes selected joy values to the 'vehicle_command_ackermann' topic. Joy[1] is the left stick vertical axis and is mapped and scaled to the vehicle speed, limited to ± 2.0 to maintain control. Joy[3] is mapped to the right stick horizontal axis and controls the steering angle and is scaled to ± 45 degrees expressed in radians (± 0.8 rad).

The odometry topic on the vehicle subscribes to our 'vehicle_command_ackermann' and causes the vehicle to move in response to our inputs.