#pragma config(Hubs, S1, HTMotor, HTMotor, HTMotor, HTMotor)

#pragma config(Sensor, S1, , sensorI2CMuxController)

#pragma config(Motor, mtr\_S2\_C2\_1, backright, tmotorTetrix, openLoop)

#pragma config(Motor, mtr\_S2\_C2\_2, frontright, tmotorTetrix, openLoop)

#pragma config(Motor, mtr\_S1\_C1\_1, backleft, tmotorTetrix, openLoop)

#pragma config(Motor, mtr\_S1\_C1\_2, frontleft, tmotorTetrix, openLoop)

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

#include "JoystickDriver.c"

//defines the buttons on the controller

task main()

{

getJoystickSettings(joystick);

//make sure joystick values are updated

while(true)

{

int x = joystick.joy1\_x2; //sideways

int y = joystick.joy1\_y2; //forward and backward

int z = joystick.joy1\_y1; //rotation

//set x y and z to the joystick values

//x is horizontal, y is vertical, 1 and 2 are different buttons

motor[frontleft]=-(y+x+z);

motor[backleft]=-(y-x+z);

motor[frontright]=(y-x-z);

motor[backright]=(y+x-z);

}

}