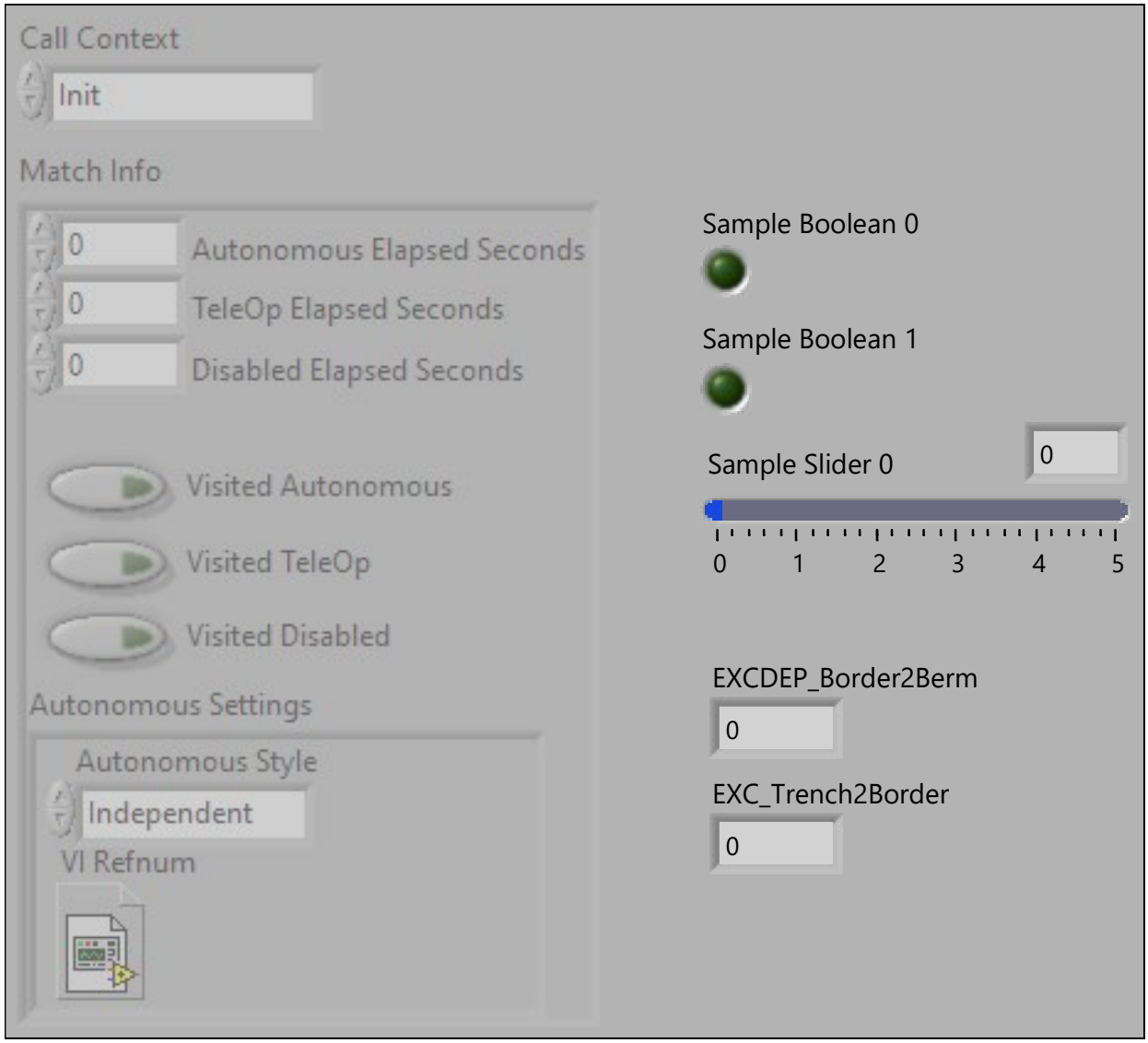
Teleop.vi
C:\Users\doggl\Documents\GitHub\RAN2023\2024RobotCode\2024StateMachineDevelopment\Teleop.vi
Last modified on 4/17/2024 at 6:21 PM
Printed on 9/5/2024 at 7:26 PM

Teleop.vi

Call Context
Match Info

This VI is called for each TeleOp packet received from the DS where the robot is not disabled. It is often used to read from the joysticks and update I/O or to update setpoints for timed control loops. It should complete and return within 20 milliseconds or it may miss DS packets.



Call Context
<B>Derived Robot State</B> returns the allowed derived robot state for the current phase of competition. Options include <B>Init</B>, <B>Execute</B>, and <B>Stop</B>.

Match Info

- **Autonomous Elapsed Seconds**
- **TeleOp Elapsed Seconds**
- **Disabled Elapsed Seconds**
- **Visited Autonomous**

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Visited TeleOp

Visited Disabled

Autonomous Settings

Autonomous Style

VI Refnum

This VI is called each time a TeleOp DS packet is received. Use it to respond to new joystick or Driver Station values.

Common tasks include reading the joysticks and updating motors, and updating setpoints for periodic loops.

You can open I/O on the FIRST Call, or in the Begin.vi.

Match Info

TeleOp Elapsed Seconds

This can help determine what has been run and for how long

Call Context

Use to differentiate between First, Last, and Intermediate calls

Each time we enter, report that we are running teleop

These are examples of reading dashboard controls from the Basic tab

DB/Button 0

DB/Button 1

DB/Slider 0

Sample Boolean 0

Sample Boolean 1

Sample Slider 0

Distance variables

EXCDEP_Border2Berm

EXC_Trench2Border