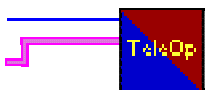


Teleop.vi
C:\Users\doggl\Documents\GitHub\RAN2023\2024RobotCode\2024StateMachineDevelopment\
Teleop.vi
Last modified on 4/17/2024 at 6:21 PM
Printed on 9/5/2024 at 7:26 PM

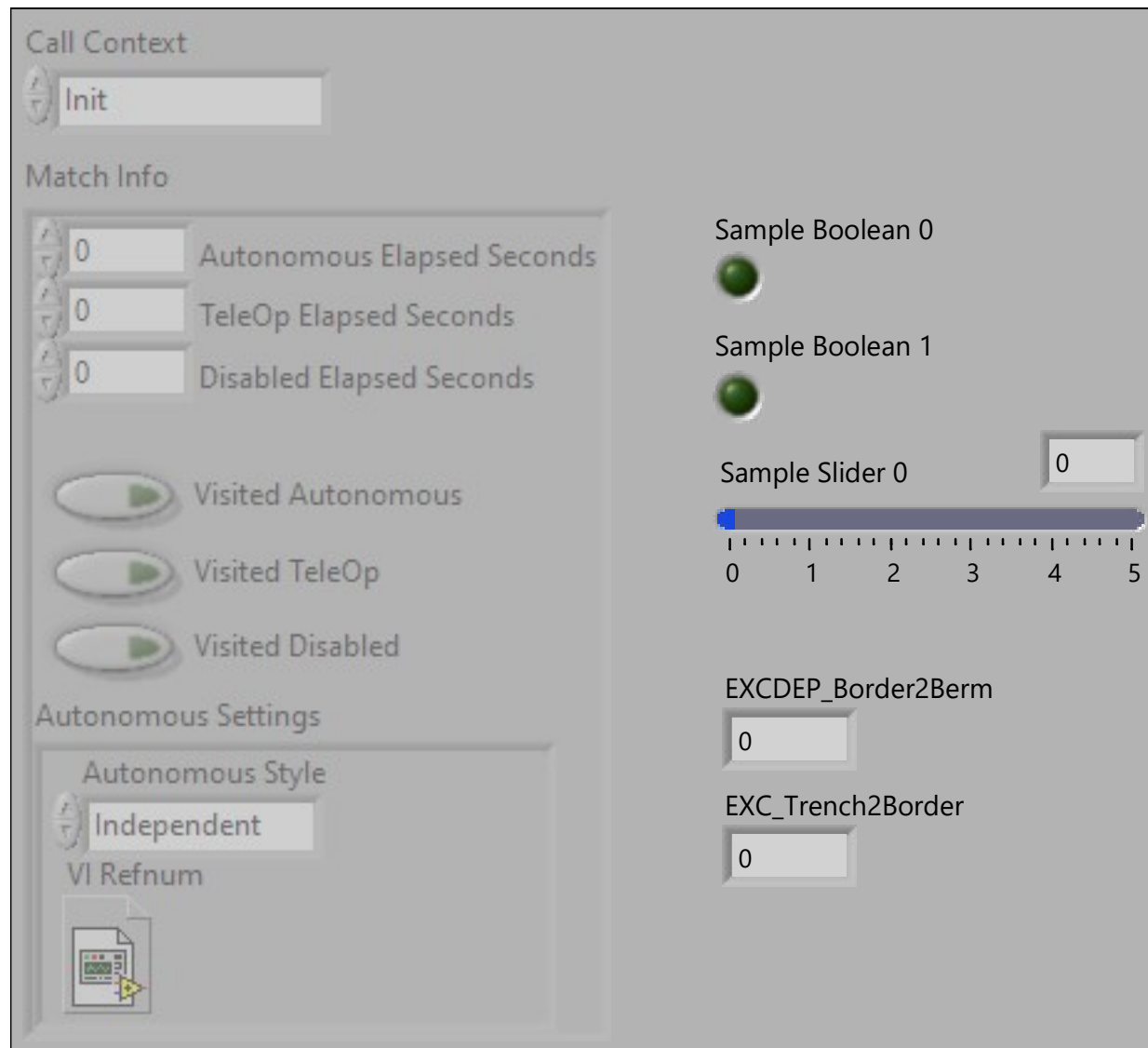
Teleop.vi

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.



The screenshot shows the front panel of the Teleop.vi. It includes a 'Call Context' section with a dropdown menu set to 'Init'. Below this is a 'Match Info' section with three numeric displays showing '0' for 'Autonomous Elapsed Seconds', 'TeleOp Elapsed Seconds', and 'Disabled Elapsed Seconds'. There are also three indicator lights labeled 'Visited Autonomous', 'Visited TeleOp', and 'Visited Disabled', all of which are currently off. The 'Autonomous Settings' section contains a dropdown for 'Autonomous Style' set to 'Independent' and a 'VI Refnum' field. On the right side, there are two 'Sample Boolean' indicators (both off), a 'Sample Slider 0' set to 0, and two numeric displays for 'EXCDEP_Border2Berm' and 'EXC_Trench2Border', both set to 0.



Call Context

Derived Robot State returns the allowed derived robot state for the current phase of competition. Options include Init, Execute, and Stop.



Match Info

 **Autonomous Elapsed Seconds**

 **TeleOp Elapsed Seconds**

 **Disabled Elapsed Seconds**

 **Visited Autonomous**



Teleop.vi

C:\Users\dogg\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



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



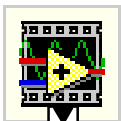
This can help determine what has been run and for how long

Call Context

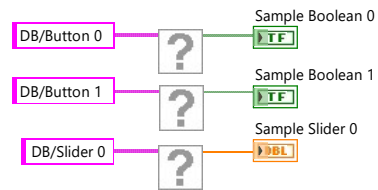


Use to differentiate between First, Last, and Intermediate calls

Each time we enter, report that we are running teleop



These are examples of reading dashboard controls from the Basic tab



Distance variables

EXCDEP_Border2Berm



EXC_Trench2Border

