Teleop.vi
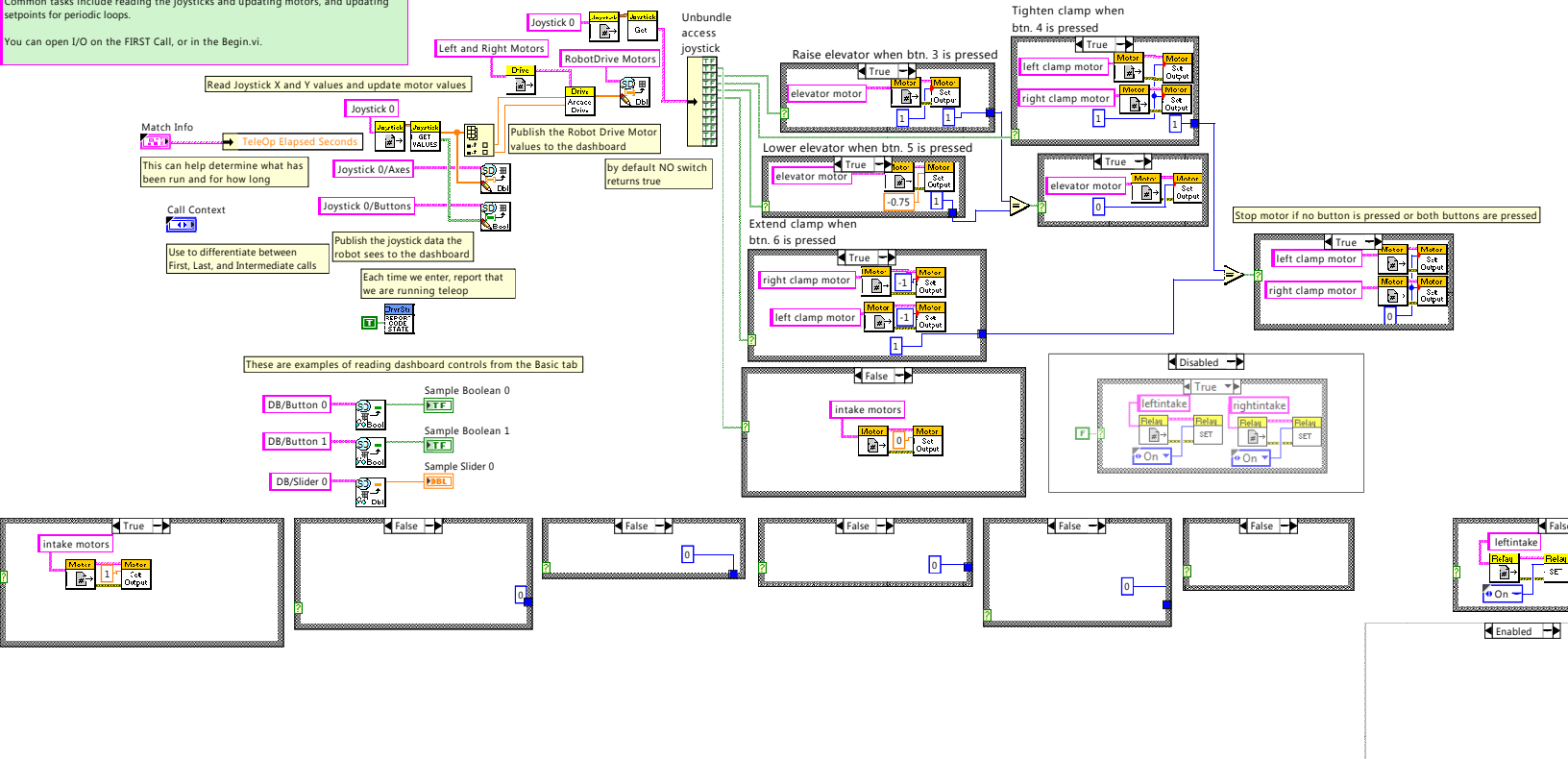C:\Users\robobibb\Documents\LabVIEW Data\2015 New Code\Teleop.vi
Last modified on 10/10/2015 at 12:01 PM
Printed on 12/9/2015 at 1:42 PM

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.

Joystick 0

Left and Right Motors

RobotDrive Motors

Read Joystick X and Y values and update motor values

Joystick 0

Match Info

TeleOp Elapsed Seconds

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

Call Context

Joystick 0/Axes

Use to differentiate between First, Last, and Intermediate calls

Joystick 0/Buttons

Publish the joystick data the robot sees to the dashboard

Each time we enter, report that we are running teleop

These are examples of reading dashboard controls from the Basic tab

Publish the Robot Drive Motor values to the dashboard

Unbundle access joystick

by default NO switch returns true

Raise elevator when btn. 3 is pressed
True
elevator motor

Lower elevator when btn. 5 is pressed
True
elevator motor
-0.75

Extend clamp when btn. 6 is pressed
True
right clamp motor
-1
left clamp motor
-1

False
intake motors

Tighten clamp when btn. 4 is pressed
True
left clamp motor
right clamp motor

True
elevator motor
0

Stop motor if no button is pressed or both buttons are pressed
True
left clamp motor
right clamp motor
0

Disabled
True
leftintake   rightintake
On   On
F

DB/Button 0   Sample Boolean 0
DB/Button 1   Sample Boolean 1
DB/Slider 0   Sample Slider 0

True
intake motors
1

False
0

False
0

False
0

False
0

False
leftintake
On

Enabled

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rightintake

Relay
SET

On

False