# Input

**Short description**

This package translates different types of manual input (joystick or keyboard) to robotcommand messages and publishes these messages on a ROS topic (/robotcommands).

**Executables**

* keyboard\_controller
* joystick\_input
* run\_input\_plugin.py

Note: start the joystick input using the launch file joysticks.launch, because it also sets the right parameters

**Dependencies**

SDL, necessary for keyboard\_controller (install: sudo apt-get install libsdl2-dev)

**Globals**

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**Params**

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**Input topics**

None, only requires user input

**Output topics**

* /robotcommands

**Details**

The keyboard controller (in combination with a running roscore and robothub) is a very easy way to test whether robots are receiving messages and responding correctly to commands.

The joystick input interface can be started using the launchfile joysticks.launch. This starts a graphical interface in which the type of joystick and the robot ID to be controlled can be selected. Also, the type of control can be selected: you can choose between normal control and keeper control. Keeper control only moves along the defense area border line, although currently this is still work in progress.