**carcontrol\_joy**

This code implement the car movements with a PlayStation3 controller.

Both Joysticks has been configured . The left one makes possible the turns to the right and left. The right one makes possible the aceleration.

The aceleration mode has been configured to have a limit speed. It increases until it reaches the top.

To run this node you have to:

**>> rosrun carcontrol\_joy control\_joy.py**

**Objetives:**

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**gps\_umd**

**nmea\_navsat\_driver**

**range\_tester ( controller\_bond.py)**

This code implement the car movements with the keyboard.

The controllers are AWSD the space bar to recover the initial position and the 1 key to exit the program.

This code has the ULTRA GREATEST THING, that consist in an emergency mode if the car lost the connection. If that happends the car automatically stops. That makes that Isa does not run chasing the car to prevent it from crashing.

To run this node you have to:

**>> rosrun range\_tester controller\_bond.py**

**Objetives:**

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**usb\_cam**

This node makes posible the adorable vision of the members of this club. The node makes the camera start to capture images, and then they are compressed to make the transmition more efficiently.

Firstly you have to run the camera node with:

>> rosparam set cv\_camara

This thing do things:

>> export LIBGL\_ALWAYS\_SOFTWARE=1

To visualize:

>> rosrun rviz rviz