```python
#!/usr/bin/env python
# -*- coding: utf-8 -*-
import wx
import xmlrpclib
import time
import sys
import pygame
import math

pygame.init()
pygame.joystick.init()

#inizate 1 joystick
joy=pygame.joystick.Joystick(0)
joy.init()
#print joystick name
print joy.get_name()
axes=joy.get_numaxes()
time.sleep(1)
pwmref=180
left=1
right=1
def Maju():
        (arah,lurus,belok,maxspeed)=get()
        maxspeed*=10
        if maxspeed<-5:
            pwmnaik=50
        elif maxspeed<0:
            pwmnaik=40
        elif maxspeed<5:
            pwmnaik=30
        elif maxspeed<10:
            pwmnaik=20
        arah*=10
        belok*=5
        pwml=0
        pwmr=0
        lurus*=10
        arah=int(arah)
        lurus=int(lurus)
        print arah,lurus,maxspeed
        if lurus==0:
            Stop()
        elif lurus<0:#maju pwmref 1800+75 max
            pwml=pwmref-lurus+arah+belok+pwmnaik
            pwmr=pwmref-lurus-arah-belok+pwmnaik
            pwml=int(pwml)
            pwmr=int(pwmr)
            left=1
            right=1
            data=ugv.manual(pwml,pwmr,left,right)
            return data
        if lurus>0:#mundur
            pwml=pwmref+lurus-arah-belok+pwmnaik
            pwmr=pwmref+lurus+arah+belok+pwmnaik
            pwml=int(pwml)
            pwmr=int(pwmr)
            left=0
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```python
59              right=0
60              data=ugv.manual(pwml,pwmr,left,right)
61          '''if maxspeed<0:
62              pwmmax=255
63          elif maxspeed>=0:
64              pwmmax=220
65          if pwml>pwmmax:
66              pwml=pwmmax
67          if pwmr>pwmmax:
68              pwmr=pwmmax'''
69              #data=ugv.manual(pwml,pwmr,1,1)
70          #print "Maju,%s,%s" % (self.pwml,self.pwmr)

72  def Stop():
73          left=1
74          right=1
75          pwml=100
76          pwmr=100
77          data=ugv.manual(pwml,pwmr,left,right)
78          print "stop"
79          return data
80          #print "Stop!,%s,%s" %(self.pwml,self.pwmr)
81  def get():
82      #print joystick name
83      axes=joy.get_numaxes()
84      axis=[0,0,0,0]
85      i=0
86      j=0
87      pygame.event.pump()
88      for i in range (axes):
89          axis[i] = joy.get_axis(i)
90      #print axis
91      return axis
92  while True:
93      ugv = xmlrpclib.ServerProxy("http://10.14.1.1:8000/")
94      data=Maju()
95      print data
96      time.sleep(0.1)
97
```