**Functions from controller\_commands.h**

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| **Syntax** | void driveControlJoysticks(int controller) |
| **Purpose** | Allows the operator to control the robot using the joystick system. The user may operate from the main or partner controller. Supports X-drives, H-drives and tank drives. |
| **Entry Conditions** | * *controller* - Represents the desired controller. Must have the value of either *MAIN* or *PARTNER*. |
| **Code**  **Example** | //control drive system with the main joystick  while(true)  driveControlJoysticks(MAIN); |

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| **Syntax** | bool isPressed(int button) |
| **Purpose** | Returns true if a button on the joystick is being pressed. |
| **Entry Conditions** | * *button* - Represents the target joystick button that is being checked to see if it is pressed. |
| **Code**  **Example** | //control a motor using a button  while(true)  {  //motor goes forward  if(isPressed(btn5D))  motor[port1] = 127;  //motor goes backward  else if(isPressed(btn5U))  motor[port1] = -127;  //motor is stopped  else  motor[port1] = 0;  } |