**UWROV Nautilus Control System Documentation**

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**Preface:**

With new control systems comes new documentation! This is our complete documentation on our system running on the Raspberry Pi.

**Architecture:**

Our main architecture will work as follows:

Internal Command Module:

Motor Command Module:

Hardware:

Robot Command Module:

Control Module:

Server API:

**Control Module:**

The control module will simply be the main control loop that will read inputs, commands, and the database to run functions based on the inputs. The control module will contain all of the high-level states of the robot such as which robot commands are running and will have access to the robot database in the Server API.

Function:

Startup functions:

* Start server
* Start Control Loop

Input:

The general Design:

**Robot Commands Module:**

**Motor Command Module:**

**Internal Command Module:**

**Hardware:**

**Server API:**