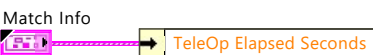# Teleop.vi
F:\Drive\Teleop.vi
Last modified on 1/17/2019 at 5:21 PM
Printed on 1/17/2019 at 8:01 PM

This VI is called each time a TeleOp DS packet is received. Use it to respond to new joystick or Driver Station values.

Common tasks include reading the joysticks and updating motors, and updating setpoints for periodic loops.

You can open I/O on the FIRST Call, or in the Begin.vi.

Match Info

TeleOp Elapsed Seconds

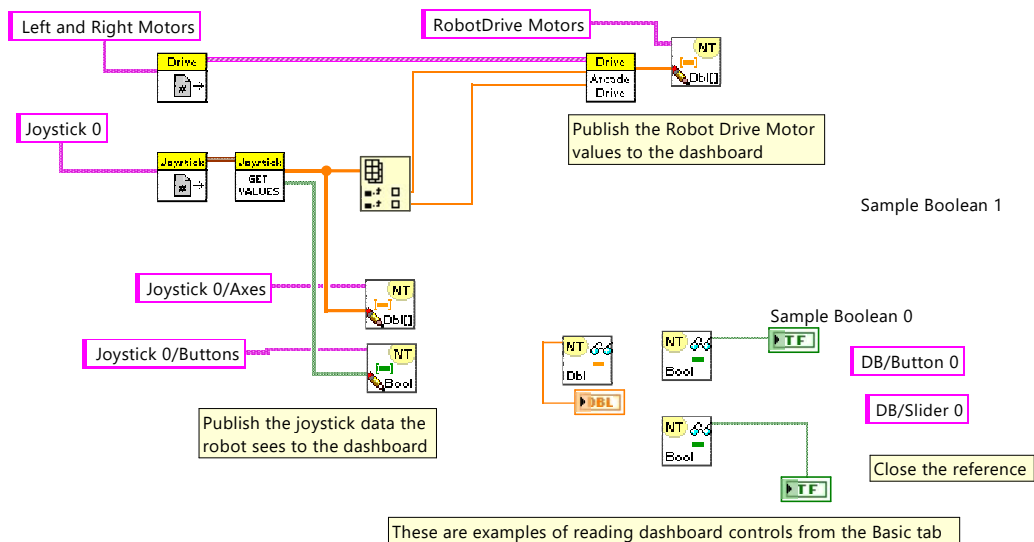This can help determine what has been run and for how long

Call Context

Use to differentiate between First, Last, and Intermediate calls

Each time we enter, report that we are running teleop

Read Joystick X and Y values and update motor values

Sample Slider 0

Left and Right Motors

RobotDrive Motors

Joystick 0

Publish the Robot Drive Motor values to the dashboard

Sample Boolean 1

Joystick 0/Axes

Sample Boolean 0

Joystick 0/Buttons

DB/Button 0

Publish the joystick data the robot sees to the dashboard

DB/Slider 0

Close the reference

These are examples of reading dashboard controls from the Basic tab

Teleop.vi

Solenoid A

Joystick 0

Index Array

Forward

Note: the compressor will automatically be handled when any solenoid is created

Reverse

Select