

# Controllers

This page is for describing how to use the manual controllers we have for the sub.

## Joystick

This is composed of two programs, `joystick_driver` and `joystick_control`. The `joystick_driver` reads the joystick and publishes the joystick's state to a topic, while `joystick_control` subscribes to this topic and publishes control messages.

Forward/back and left/right cause the sub to move forward/back, left/right as expected. Twisting the joystick controls the sub's yaw. The hat affects pitch and roll, while pulling the trigger resets the sub to a neutral orientation. The throttle is used for controlling the depth of the sub, with the min and max depths are controlled by settings in the parameter server.

From:

<http://robosub-vm.eecs.wsu.edu/wiki/> - **Palouse RoboSub Technical Documentation**

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<http://robosub-vm.eecs.wsu.edu/wiki/cs/controllers/start?rev=1482867904>



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