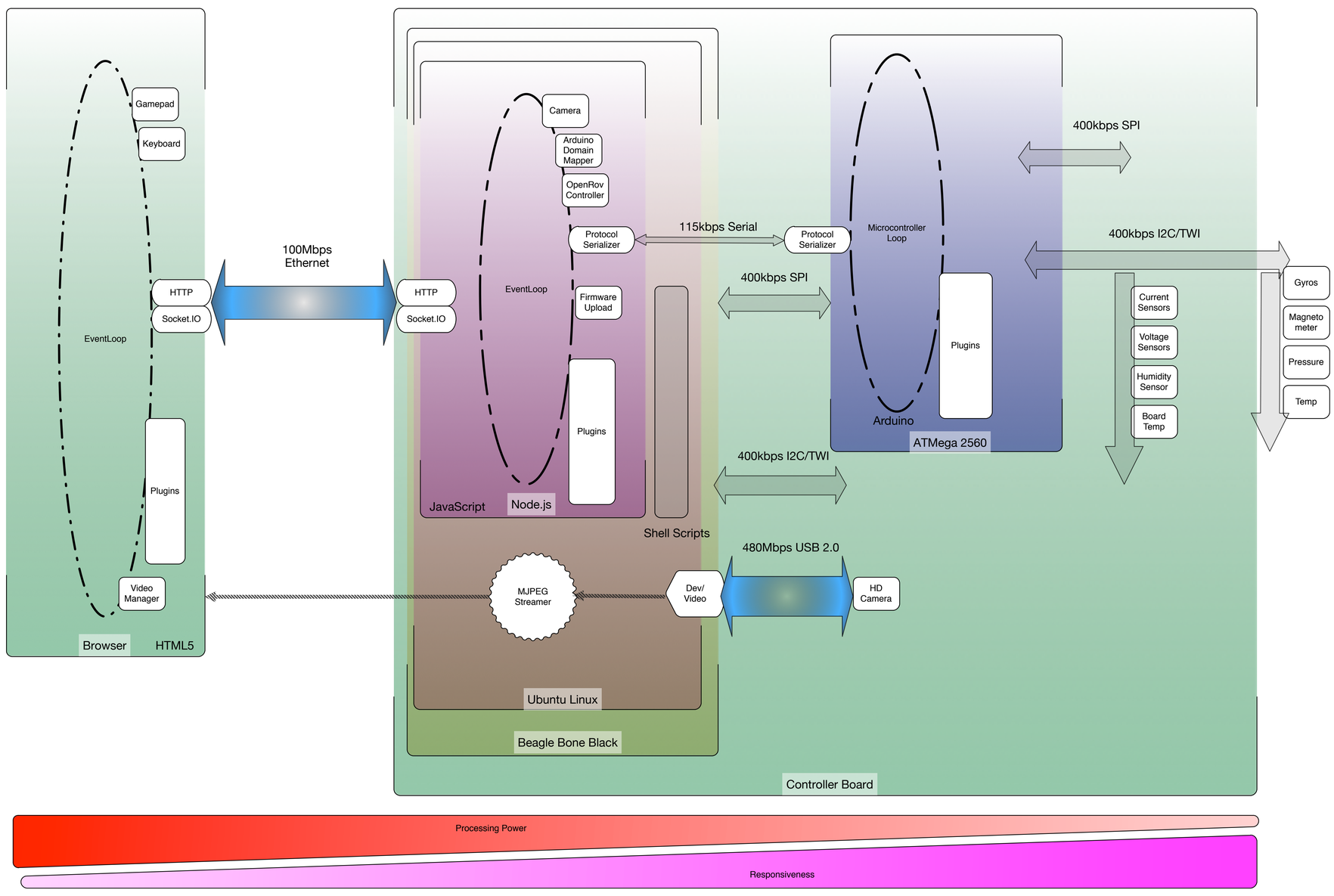

Base APIS

	div#navtoolbar div#servoTilt ul#menuitems a#show-settings a#show-diagnostics div#main-row div#outter-videocontainer div#video-container div#video canvas#video-canvas div#rov_status_panel div#rov_buttonPanel div#footer div#footercontent div#settings div#diagnostic div#keyboardInstructions EventEmitter2 cockpitEventEmitter	<-VideoStarted <-ViedoStopped <-rovsys(bitarray)	rcap() reportSettings() rmtrmod() updateSettings(smoothingIncriment,deadzone_neg,deadzone_pos,water_type) <-status(ver,TSET,CAPA,cmd,log,hdgd,deap,pitc,roll,yaw,fthr

Plugins APIS

Tank Control			
Horizon			
FPS Counter			
Touch Control			
Scaling Distance Display			
Compass			
Board Sensors			
XMPP Talk			
Camera Tilt			tilt(milliseconds)
Telemetry		<-status(name/:value pair string)	
Pilot		esc_poweron(), esc_poweroff() holdHeading_toggle() ,holdDepth_toggle() holdHeading_on(degrees) ,holdDepth_on(depth_meters) thro(-1..1), yaw(-1..1), lift(-1..1)	escp(0/1) holdHeading_toggle(), holdDepth_toggle() holdHeading_on(degrees) holdDepth_on(centimeters) thro(-1..1), yaw(-1..1), lift(-1..1)
Motor Diags		callibrate_escs() <-mcal() motor_test(port:Milliseconds, vertical:Milliseconds, port:Milliseconds)	mcal()
Thrusters			mtrmod(port%,vertical%,starbord%,nport%,nvertical%,starbord%) go(port:milliseconds,vertical:millseconds,starboard:milliseconds,smoothingboolean) stop() start()
Photo Capture		snapshot() <-photo-added(relative_path_to_file)	
Motor Controller			
Serial Inspector		<-serial-recieved(text_data) SerialMonitor_toggle_rawSerial()	
Lights			ligt(0..1)
Adv Camera Control			
Lasers			claser(0..1)
Dive Profile			
IMU		<-navdata(roll,pitc,yaw,thrust,deapth,hdgd)	
Fly By Wire			
Black Box			
Cape Status		<- status(time, bout, iout, cpuUsage, LIGP	
Arduino Firmware			