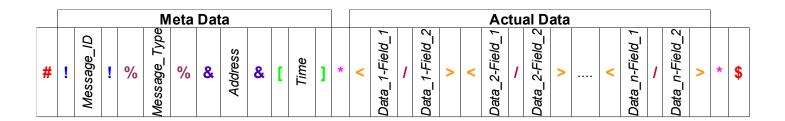
## Morpho-Motion communication protocol



- Message\_ID: A unique ID for each message sent out either from the PC or Skymega. [Unsigned long]
- Message Type:
  - 0: Command to move servo motor to a specific angle mentioned [PC to Skymega].
  - 1: Requesting current servo position [PC to Skymega].
  - 2: Message containing servo position data with time read at [Skymega to PC].
  - 3: Requesting time [PC to Skymega].
  - 4: Message containing current time [Skymega to PC].
- Address:
  - 0: Servo 1
  - 1: Servo 2
  - 2: Servo 3
  - 3: Servo 4
  - 4: All servos
- Time: Contains the time [in milliseconds] at which the servo position(s) mentioned in the message frame was/were read at. [Unsigned long].
- Time: Contains the time [in milliseconds] at which the message frame was constructed. [Unsigned long].
- Data: Contains the actual data [Servo angle to be actuated with or current servo position]
  - Field 1: Raw servo position data. [Signed long]
  - Field\_2: Number of values after the decimal point, data in Field\_1 contains. [Unsigned int] Processed data = Field\_1/10^Field\_2.
  - Field\_2: Signed time difference between value in field *Time* and the time at which the respective Servo's POT data was read. [Signed long]