void walkForward(){

while(!(Command == 10)){

//=================== STOP Check =========================//

if(Serial.available() > 0){ // Checks whether data is comming from the serial port

Command = Serial.read(); // Reads the data from the serial port ans saves it

if(Command == 10) break;

}

//========================================================//

myServos.setPWM(TopRFront, 0, map(180 - 150, 0, 180, 130, 600));

myServos.setPWM(BottomRFront, 0, map(180 - 90, 0, 180, 130, 600));

myServos.setPWM(TopLFront, 0, map(150, 0, 180, 130, 600));

myServos.setPWM(BottomLFront, 0, map(90, 0, 180, 130, 600));

myServos.setPWM(TopRBack, 0, map(180 - 150, 0, 180, 130, 600));

myServos.setPWM(BottomRBack, 0, map(180 - 90, 0, 180, 130, 600));

myServos.setPWM(TopLBack, 0, map(150, 0, 180, 130, 600));

myServos.setPWM(BottomLBack, 0, map(90, 0, 180, 130, 600));

delay(150);

//=================== STOP Check =========================//

if(Serial.available() > 0){ // Checks whether data is comming from the serial port

Command = Serial.read(); // Reads the data from the serial port ans saves it

if(Command == 10) break;

}

//========================================================//

//Leg Front Right Forward

myServos.setPWM(BottomRFront, 0, map(180 - 80, 0, 180, 130, 600));

myServos.setPWM(TopRFront, 0, map(180 - 70, 0, 180, 130, 600));

delay(150);

myServos.setPWM(BottomRFront, 0, map(180 - 120, 0, 180, 130, 600));

//delay(300);

//=================== STOP Check =========================//

if(Serial.available() > 0){ // Checks whether data is comming from the serial port

Command = Serial.read(); // Reads the data from the serial port ans saves it

if(Command == 10) break;

}

//========================================================//

//Leg Back Left Forward

myServos.setPWM(BottomLBack, 0, map(80, 0, 180, 130, 600));

myServos.setPWM(TopLBack, 0, map(70, 0, 180, 130, 600));

delay(150);

myServos.setPWM(BottomLBack, 0, map(120, 0, 180, 130, 600));

delay(150);

//=================== STOP Check =========================//

if(Serial.available() > 0){ // Checks whether data is comming from the serial port

Command = Serial.read(); // Reads the data from the serial port ans saves it

if(Command == 10) break;

}

//========================================================//

//Both Legs pulling back

myServos.setPWM(TopRFront, 0, map(180 - 150, 0, 180, 130, 600));

myServos.setPWM(TopLBack, 0, map(150, 0, 180, 130, 600));

delay(100);

myServos.setPWM(BottomRFront, 0, map(180 - 90, 0, 180, 130, 600));

myServos.setPWM(BottomLBack, 0, map(90, 0, 180, 130, 600));

delay(100);

//=================== STOP Check =========================//

if(Serial.available() > 0){ // Checks whether data is comming from the serial port

Command = Serial.read(); // Reads the data from the serial port ans saves it

if(Command == 10) break;

}

//========================================================//

myServos.setPWM(BottomLFront, 0, map(80, 0, 180, 130, 600));

myServos.setPWM(TopLFront, 0, map(70, 0, 180, 130, 600));

delay(150);

myServos.setPWM(BottomLFront, 0, map(120, 0, 180, 130, 600));

//delay(300);

//=================== STOP Check =========================//

if(Serial.available() > 0){ // Checks whether data is comming from the serial port

Command = Serial.read(); // Reads the data from the serial port ans saves it

if(Command == 10) break;

}

//========================================================//

myServos.setPWM(BottomRBack, 0, map(180 - 80, 0, 180, 130, 600));

myServos.setPWM(TopRBack, 0, map(180 - 70, 0, 180, 130, 600));

delay(150);

myServos.setPWM(BottomRBack, 0, map(180 - 120, 0, 180, 130, 600));

delay(150);

//=================== STOP Check =========================//

if(Serial.available() > 0){ // Checks whether data is comming from the serial port

Command = Serial.read(); // Reads the data from the serial port ans saves it

if(Command == 10) break;

}

//========================================================//

myServos.setPWM(TopLFront, 0, map(150, 0, 180, 130, 600));

myServos.setPWM(TopRBack, 0, map(180 - 150, 0, 180, 130, 600));

delay(100);

myServos.setPWM(BottomLFront, 0, map(90, 0, 180, 130, 600));

myServos.setPWM(BottomRBack, 0, map(180 - 90, 0, 180, 130, 600));

delay(100);

}

}