

PGNs	230	234	254	32613	32614	32616	32618	211
	VR data to RC from AGIO	section status to AOG from RC	AutoSteer Data to RC from AGIO	rate applied from arduino to RC	settings to arduino from RC	PID to arduino from RC	Switch Positions to RC from switch box	IMU
0	128	128	128	101	102	104	106	128
1	129	129	129	127	127	127	127	129
2	source	source	source	rate sensor ID low 4 bits, arduino ID high 4 bits	rate sensor ID low 4 bits, arduino ID high 4 bits	rate sensor ID low 4 bits, arduino ID high 4 bits	auto, Mstr On, Mstr Off, Rate Up, Rate Down	source, 0x79 (121)
3	AGIO PGN 0xE6 (230)	AGIO PGN 0xEA (234)	AGIO PGN 0xFE (254)	rate applied Lo, 10 X actual	relay Lo, 0-7	Kp	sw0, sw1, sw2, sw3, sw4, sw5, sw6, sw7	AGIO PGN 0xDE (211)
4	length	length	length	rate applied Mid	relay Hi, 8-15	MinPWM	sw8, sw9, sw10, sw11, sw12, sw13, sw14, sw15	Heading Lo X 10
5	rate 0 Lo	Main	speed Lo - kmh X 10	rate applied Hi	rate set Lo, 10 X actual	LowMax	CRC	Heading Hi
6	rate 0 Hi	-	speed Hi	acc. Quantity Lo, 10 X actual	rate set Mid	HighMax		Roll Lo X 10
7	rate 1 Lo	-	status	acc. Quantity Mid	rate set Hi	Deadband		Roll Hi
8	rate 1 Hi	Number of sections	steer angle Lo	acc. Quantity Hi	flow Cal Lo	BrakePoint		Gyro Lo X 10
9	rate 2 Lo	On Group 0	steer angle Hi	PWM Lo	flow Cal Hi, 100 X actual	TimedAdjustment		Gyro Hi
10	rate 2 Hi	Off Group 0	-	PWM Hi	Commands	Ki		Pitch Lo X 10
11	rate 3 Lo	On Group 1	Relay Lo	Status byte	power relay Lo, 0-7	CRC		Pitch Hi
12	rate 3 Hi	Off Group 1	Relay Hi	CRC	power relay Hi, 8-15			CRC
13	rate 4 Lo	CRC	CRC	byte 11	CRC			
14	rate 4 Hi			bit 0, sensor 0 connected	byte 10			
15	CRC			bit 1, sensor 1 connected	bit 0, reset acc. Quantity			
16					bit 1/2, control type 0-3			
					bit 3, simulate flow			
					bit 4, pulses to measure			
					bit 5, Auto On			
					bit 6, Debug On			

	32619	32620	32621	32622	32623	32624	32625	32626	32627
	Wifi section switches to arduino	Section switch IDs to arduino from RC	pressures to RC from arduino	Teensy Config	Teensy Config 2	Teensy Pins	Nano Config	Nano Pins	Switchbox Pins
0	107	108	109	110	111	112	113	114	115
1	127	127	127	127	127	127	127	127	127
2	Master On	sec 0, 1	arduino ID	Receiver, 0 none, 1 SimpleRTK2B, 2 Sparkfun	Minimum speed	Steer DIR	ModuleID	Flow1	Auto
3	sw0, sw1, sw2, sw3, sw4, sw5, sw6, sw7	sec 2, 3	sensor 0, Lo	NMEA serial port	Maximum speed	Steer PWM	SensorCount	Flow2	Master On
4	sw8, sw9, sw10, sw11, sw12, sw13, sw14, sw15	sec 4, 5	sensor 0, Hi	RTCM serial port	Pulse Cal X 10, Lo	Steer switch	IP address	Dir1	Master Off
5	CRC	sec 6, 7	sensor 1, Lo	RTCM UDP port #, Lo	pulse Cal X 10, Hi	Wheel angle sensor	Commands	Dir2	Rate Up
6	ex: sec 0 is low 4 bits, sec 1 is high 4 bits of byte 2	sec 8, 9	sensor 1, Hi	RTCM UDP port #, Hi	ADS1115 WAS pin	Steer relay	CRC	PWM1	Rate Down
7		sec 10, 11	sensor 2, Lo	IMU, 0 none, 1 Sparkfun, 2 CMPS14, 3 Adafruit, 4 serial	RS485 port number	Work switch	Byte 5:	PWM2	IP address
8		sec 12, 13	sensor 2, Hi	IMU read delay	Module ID	Current sensor	UseMCP23017	Relay 1	SW0
9		sec 14,15	sensor 3, Lo	IMU report interval	Commands	Pressure sensor	Relay on signal	Relay 2	SW1
10		CRC	sensor 3, Hi	WAS zero offset, Lo	CRC	Encoder	flow on signal	Relay 3	SW2
11		CRC	WAS zero offset, Hi	Byte 9:	Rate DIR		Relay 4	SW3	
12		RelayControl	bit 0, Use rate control	Rate PWM		Relay 5	SW4		
13		IP address	bit 1, use ADS1115	Speed pulse		Relay 6	SW5		
14		CRC	bit 2, Relay on signal	RS485 send enable		Relay 7	SW6		
15			bit 3, flow on signal	CRC		Relay 8	SW7		
16			bit 4, Swap pitch for roll			Relay 9	SW8		
17			bit 5, Invert roll			Relay 10	SW9		
18		bit 6, GyroOn			Relay 11	SW10			
19		bit 7, Use Actuator			Relay 12	SW11			
20					Relay 13	SW12			
21					Relay 14	SW13			
22					Relay 15	SW14			
23					Relay 16	SW15			
24					CRC	CRC			