PGNs	230	234	235	254	32613	32614	32616	32618	32619
	VR data to RC from AGIO	section status to AOG from RC	section widths from AOG	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	Wemos D1 mini switches
0	128	128	128	128	101	102	104	106	107
1	129	129	129	129	127	127	127	127	127
2	source	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	Master On
3	AGIO PGN 0xE6 (230)	AGIO PGN 0xEA (234)	AGIO PGN 0xEB (235)	AGIO PGN 0xFE (254)	rate applied Lo, 1000 X actual	relay Lo, 0-7	Kp	sw0, sw1, sw2, sw3, sw4, sw5, sw6, sw7	sw0, sw1, sw2, sw3, sw4, sw5, sw6, sw7
4	length	length	length	length	rate applied Mid	relay Hi, 8-15	MinPWM	sw8, sw9, sw10, sw11, sw12, sw13, sw14, sw15	sw8, sw9, sw10, sw11, sw12, sw13, sw14, sw15
5	rate 0 Lo	Main	bytes 5-36 sections 0-15	speed Lo - kmh X 10	rate applied Hi	rate set Lo, 1000 X actual	LowMax	CRC	CRC
6	rate 0 Hi	-	2 bytes per section, width in cm	speed Hi	acc. Quantity Lo, 10 X actual	rate set Mid	HighMax		
7	rate 1 Lo	-	byte 37 # of sections	status	acc. Quantity Mid	rate set Hi	Deadband		
8	rate 1 Hi	Number of sections	byte 38 CRC	steer angle Lo	acc. Quantity Hi	flow Cal Lo, 1000 X actual	BrakePoint		
9	rate 2 Lo	On Group 0		steer angle Hi	PWM Lo	flow cal Mid	TimedAdjustment		
10	rate 2 Hi	Off Group 0		-	PWM Hi	flow Cal Hi	Ki		
11	rate 3 Lo	On Group 1		Relay Lo	Status byte	Commands	CRC		
12	rate 3 Hi	Off Group 1		Relay Hi	CRC	power relay Lo, 0-7			
13	rate 4 Lo	CRC		CRC	**byte 11**	power relay Hi, 8-15			
14	rate 4 Hi				bit 0, sensor 0 connected	Calibration PWM			
15	CRC				bit 1, sensor 1 connected	CRC			
16						**byte 11**			
						bit 0, reset acc. Quantity			
						bit 1/2, control type 0-3			
						bit 3, simulate flow			
						bit 4, pulses to measure			
						bit 5, Auto On			
						bit 6, Debug On			
						bit 7, calibration on			

PGNs	32621	32622	32623	32624	32625	32626	32627	32628	32500	32501	32502	32503
	pressures to RC from arduino	Teensy Config	Teensy Config 2	Teensy Pins	Nano Config	Nano Pins	Switchbox Pins	Wemos D1 Mini analog read	Teensy RC, receive config	weight from scale	IP addresses	Wifi status
0	109	110	111	112	113	114	115	116	244	245	246	247
1	127	127	127	127	127	127	127	127	126	126	126	126
2	arduino ID	Receiver, 0 none, 1 SimpleRTK2B, 2 Sparkfun	Minimum speed	Steer DIR	ModuleID	Flow1	Auto	AIN0 Lo	ID	rate sensor ID low 4 bits, arduino ID high 4 bits	Ethernet IP part2	RSSI
3	sensor 0, Lo	NMEA serial port	Maximum speed	Steer PWM	SensorCount	Flow2	Master On	AIN0 Hi	SensorCount	weight byte 0	Ethernet IP part3	Status
4	sensor 0, Hi	RTCM serial port	Pulse Cal X 10, Lo	Steer switch	IP address	Dir1	Master Off	AIN1 Lo	IPpart3	weight byte 1	Wifi IP part2	DebugVal1
5	sensor 1, Lo	RTCM UDP port #, Lo	pulse Cal X 10, HI	Wheel angle sensor	Commands	Dir2	Rate Up	AIN1 Hi	Relay On Signal	weight byte 2	Wifi IP part3	CRC
6	sensor 1, Hi	RTCM UDP port #, Hi	Analog Method	Steer relay	CRC	PWM1	Rate Down	AIN2 Lo	Flow On Direction	weight byte 3	CRC	Byte 3 - bit 0 wifi connected
7	sensor 2, Lo	IMU, 0 none, 1 Sparkfun, 2 CMPS14, 3 Adafruit, 4 serial	RS485 port number	Work switch	**Byte 5:**	PWM2	IP address	AIN2 Hi	Relay Control Type 0-5	CRC		
8	sensor 2, Hi	IMU read delay	Module ID	Current sensor	UseMCP23017	Relay Pins 0-15, bytes 8-24	switches 0-15, bytes 8-24	AIN3 Lo	Wemos Serial Port			
9	sensor 3, Lo	IMU report interval	Commands	Pressure sensor	Relay on signal	byte 25, CRC	byte 25, CRC	AIN3 Hi	Sensor 0, Flow pin			
10	sensor 3, Hi	WAS zero offset, Lo	CRC	Encoder	flow on signal			CRC	Sensor 0, Dir pin			
11	CRC	WAS zero offset, Hi	**Byte 9:**	Rate DIR					Sensor 0, PWM pin			
12		RelayControl	bit 0, Use rate control	Rate PWM					Sensor 1, Flow pin			
13		IP address	bit 1, use TB6612	Speed pulse					Sensor 1, Dir pin			
14		CRC	bit 2, Relay on signal	RS485 send enable					Sensor 1, PWM pin			
15			bit 3, flow on signal	CRC					Relay Pins 0-15, bytes 15-30			
16			bit 4, Swap pitch for roll						byte 31, CRC			
			bit 5, Invert roll									
			bit 6, GyroOn									
			bit 7, Use Actuator									