**Transmission Protokoll**

Byte 0:

Bit7-4: Motor 0-8, 9 = All

Bit3-0: Mode

Mode 1: Velocity

Byte 1: Velocity [-100 - 100]

End

Mode 2: Position

Byte 1,2,3,4 -> int32\_t Positon

Byte 5 -> Velocity [-100 - 100]

Byte 6-> 0 == now

1 == wait for all and then synchron

~~Mode 3: Curve Parameter:~~

~~Byte 1:~~

~~Bit7-4: Point no.~~

~~Bit1: enabled/disabled~~

~~Bit0: linear/spline~~

~~Byte2-5: position~~

~~Byte6-8: gradient~~

Mode 4: Set Time

Mode 5: Set Pictures

Mode 6: Testrun/ Cycle/Pause/ Start//Stop

1 2 3 4 5

Mode 7: Send Curve Points

(point, linear/x5, position)

Mode 8: Get mintime;

Mode 9: Toggle Motor On/Off

Mode 10: return Position and Motor Status

Mode 11: return Battery Status

Byte 9: Checksum

if: checksum false checksumcounter ++

if chekcksum counter == 10; reinit

**Sendback:**

Byte 0 = 200 Gotdata

Byte 0 = 201 Send minimaltime

Byte[1-4]

Byte = 202 Byte 1,2 Bat1

Byte 3,4 Bat2