```
}

//*************************************************************************************************
//*************************************************************************************************

void calibrateThrottle () {
   //This function establishes min and max throttle values_____________________________
  pinMode (PullDownPin, INPUT);
  digitalWrite(PullDownPin, HIGH);
  pinMode(LEDPin, OUTPUT);
  while (digitalRead(PullDownPin) == HIGH)  {
   digitalWrite(LEDPin, LOW);
   delay(500);
   digitalWrite(LEDPin, HIGH);
   delay(500);
  }
  analogReadResolution(Res);
  minThrottle = analogRead(throttlePin);
  delay(ADC_DELAY);
  minThrottle = analogRead(throttlePin);
  delay(ADC_DELAY);
  #if DEBUG
    Serial.print("minThrottle = ");
    Serial.print(minThrottle);
  #endif
  digitalWrite(LEDPin, LOW);
  delay(1000);
  while (digitalRead(PullDownPin) == LOW)  {
   digitalWrite(LEDPin, LOW);
   delay(500);
   digitalWrite(LEDPin, HIGH);
   delay(500);
  }
  analogReadResolution(Res);
  maxThrottle = analogRead(throttlePin);
  delay(ADC_DELAY);
  maxThrottle = analogRead(throttlePin);
  delay(ADC_DELAY);
  maxThrottle = (maxThrottle + 10);
  #if DEBUG
    Serial.print(".......maxThrottle = ");
    Serial.println(maxThrottle);
  #endif
  digitalWrite(LEDPin, LOW);
  delay(500);
}

//*************************************************************************************************
//*************************************************************************************************

void calibrateSteering () {
   //This function establishes min and max throttle values_____________________________
  pinMode (PullDownPin, INPUT);
  digitalWrite(PullDownPin, HIGH);
  pinMode(LEDPin, OUTPUT);
  while (digitalRead(PullDownPin) == HIGH)  {
   digitalWrite(LEDPin, LOW);
   delay(200);
   digitalWrite(LEDPin, HIGH);
```