

```

292 }
293
294
295 //*****
296 //*****
297
298 void calibrateThrottle () {
299     //This function establishes min and max throttle values_____
300     pinMode (PullDownPin, INPUT);
301     digitalWrite(PullDownPin, HIGH);
302     pinMode(LEDPin, OUTPUT);
303     while (digitalRead(PullDownPin) == HIGH) {
304         digitalWrite(LEDPin, LOW);
305         delay(500);
306         digitalWrite(LEDPin, HIGH);
307         delay(500);
308     }
309     analogReadResolution(Res);
310     minThrottle = analogRead(throttlePin);
311     delay(ADC_DELAY);
312     minThrottle = analogRead(throttlePin);
313     delay(ADC_DELAY);
314     #if DEBUG
315         Serial.print("minThrottle = ");
316         Serial.print(minThrottle);
317     #endif
318     digitalWrite(LEDPin, LOW);
319     delay(1000);
320     while (digitalRead(PullDownPin) == LOW) {
321         digitalWrite(LEDPin, LOW);
322         delay(500);
323         digitalWrite(LEDPin, HIGH);
324         delay(500);
325     }
326     analogReadResolution(Res);
327     maxThrottle = analogRead(throttlePin);
328     delay(ADC_DELAY);
329     maxThrottle = analogRead(throttlePin);
330     delay(ADC_DELAY);
331     maxThrottle = (maxThrottle + 10);
332     #if DEBUG
333         Serial.print(".....maxThrottle = ");
334         Serial.println(maxThrottle);
335     #endif
336     digitalWrite(LEDPin, LOW);
337     delay(500);
338 }
339
340 //*****
341 //*****
342
343 void calibrateSteering () {
344     //This function establishes min and max throttle values_____
345     pinMode (PullDownPin, INPUT);
346     digitalWrite(PullDownPin, HIGH);
347     pinMode(LEDPin, OUTPUT);
348     while (digitalRead(PullDownPin) == HIGH) {
349         digitalWrite(LEDPin, LOW);
350         delay(200);
351         digitalWrite(LEDPin, HIGH);

```