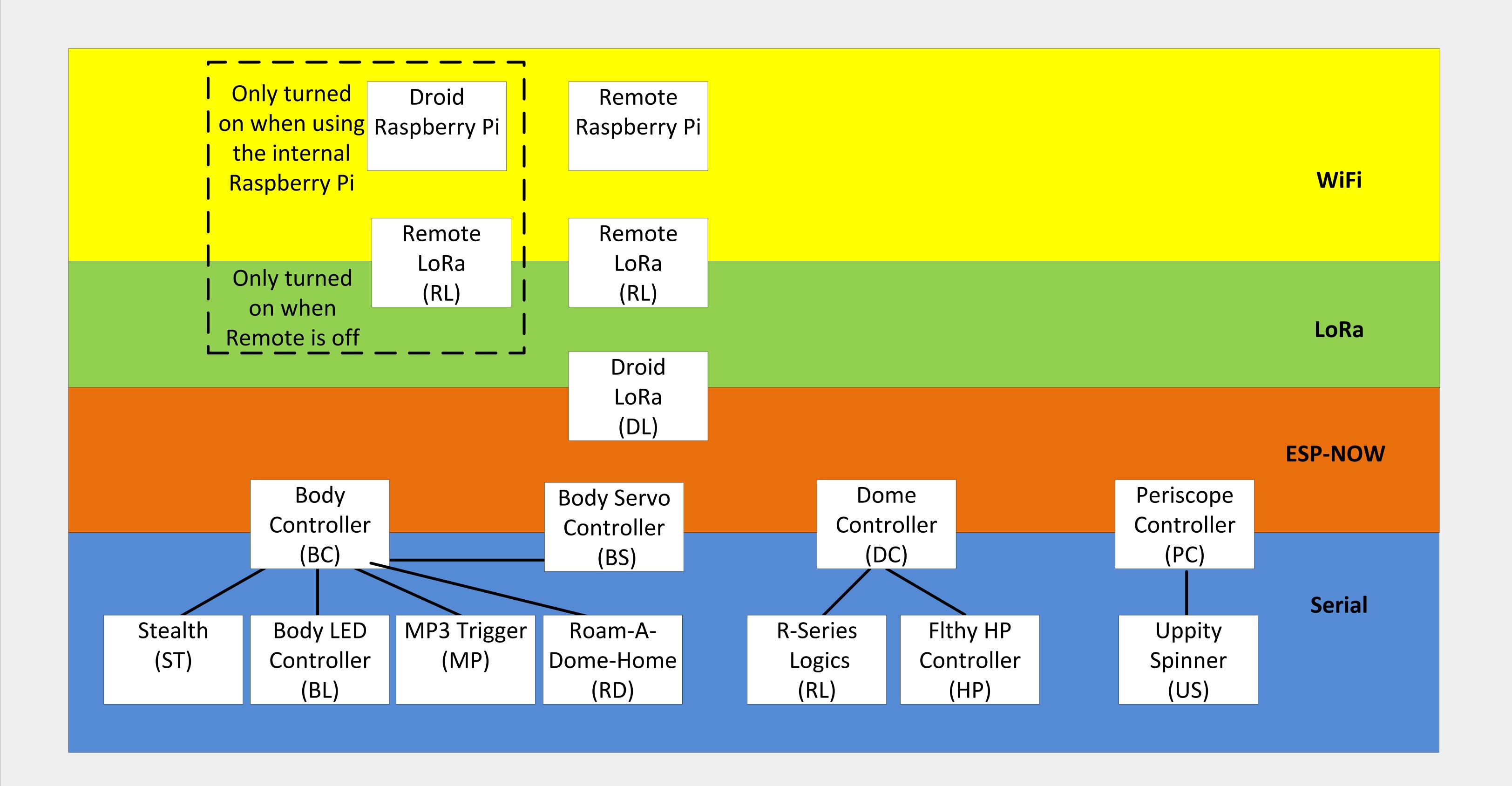


Actions Details		Details		Details	Actions	Detai	ils Actions	Details
Open/Close Dome 1 – Opens the Dome 2 – Changes the Camaera Lens LED Colors to a random color each time it closes a few panels 3 – Sets the HP's to random pulse	Right, Right	Double Click to get To the Details Page	HP Rainbow 1 - Waves the Dome Panels 2 - Flashes the Camera LEDs to Random Colors, 3 - Turns the HP LEDs to Rainbow	Double Click to get To the Details Page	Utility Arms Open/Close 1 – Opens and closes the Utility Arms Butt	Double Click To the Detail	to get	
Quick Wave 1 – Opens the Dome panels 2 – Changes the Camera Lens LED Colors to a random color each time it closes a few panels 3 – Changes the HPs to a random color each time it runs through a cycle of opening and closing	Left, Left	Double Click Double Click to get To the Details Page	HP Cyclone Blue 1 - Waves the Dome Panels 2 - Flashes the Camera LEDs to Random Colors, 3 - Turns the HP LEDs to Rainbow	Double Click	Button 7 Button 6	Button 2 Button 1		
Random Jittery Wave 1 – Opens the Dome panels 2 – Changes the Camera Lens LED Colors to a random color each time it closes a few panels 3 – Changes the HPs to a random color each time it runs through a cycle of opening and closing	Left, Right,	Double Click Double Click to get To the Details Page	HP Random Color Pulse 1 – Pulses the HP's a random Color at medium speed Down, L	Double Click Double Click to get To the Details Page	Button 8Button 9	Sutton 3		
	Right, Left,		HP Leia Message 1 – Plays the HP's at the Leia function Up. Dov			Button 4		
Wave 1 1 - Waves the Dome Panels 2 - Flashes the Camera LEDs to Random Colors, 3 - Turns the HP LEDs to Rainbow	Right, Right, Right	Double Click Double Click to get To the Details Page						
Wave 2 1 - Waves the Dome Panels 2 - Flashes the Camera LEDs to Random Colors, 3 - Turns the HP LEDs to Rainbow	Left, Left	Double Click Double Click to get To the Details Page						
	Left, Right, Left							
	Right, Left, Right							
							J	

Back to Quick Refer	Gesture	Stealth Config.txt	Body Servo Expander I2C = 9	Body Arduino Pro Mini I2C = 8	Body Arduino Mega I2C = 7	Dome Expander I2C = 10	Flthy HP I2C = 25	HP Servo Board I2C = 65	Teeces (Serial)	Teeces (Serial)
			Space Holer							



Back to Quick Reference Action	Gesture	Stealth Config.txt	Body Servo Expander I2C = 9	Body Arduino Pro Mini I2C = 8	Body Arduino Mega I2C = 7	Dome Servo Expander I2C = 10	Flthy HP I2C = 25	HP Servo Board I2C = 65	Teeces (Serial)	Dome Button Cntr I2c = 11
Open/Close Dome 1 – Opens the Dome 2 – Changes the Camaera Lens LED Colors to a random color each time it closes a few panels 3 – Sets the HP's to random pulse	Right, Right	g=656,4,10,5				case 5: OpenClosePanels(); break; void OpenClosePanels() { //digitalWrite(STATUS_LED, HIGH); // turn on STATUS LED so we can visually see we got the command on the board //Open or close All Pie Panels				
						Serial.print("Pie Panels: "); colorWipe(C_RED, 255); // Red if (panelsOpen) { // Close the Pie Panels Serial.println("Closing"); panelsOpen=false; // Attach to PANELS so we can move them Servos[LTL1].attach(LITTLE_PANEL_1_OF_3); Servos[LTL2].attach(LITTLE_PANEL_2_OF_3); Servos[LTL3].attach(LITTLE_PANEL_3_OF_3); Servos[MED1].attach(MED_PANEL_1_OF_2); Servos[MED2].attach(MED_PANEL_2_OF_2); Servos[MED2].attach(MED_PANEL_1_OF_2); Servos[LRG1].attach(PIE1_SERVO_PIN); Servos[PIE3].attach(PIE1_SERVO_PIN); Servos[PIE3].attach(PIE3_SERVO_PIN); Servos[PIE3].attach(PIE3_SERVO_PIN); Servos[PIE4].attach(PIE4_SERVO_PIN);				
						Servos[PIE3].attach(PIE3_SERVO_PIN); Servos[PIE3].attach(PIE4_SERVO_PIN); // Close them in a non-sequencial order and not at the same time to make it more interesting // Basically 2, then 2 Servos[PIE3].write(NEUTRAL,CLOSESPEED); colorWipe(basicColors[random(1,10)], 255); // Turn Camera Lens LED Random Colors Servos[PIE3].write(NEUTRAL,CLOSESPEED,true); // wait Servos[PIE4].write(NEUTRAL,CLOSESPEED); colorWipe(basicColors[random(1,10)], 255); // Turn Camera Lens LED Random Colors Servos[PIE2].write(NEUTRAL,CLOSESPEED); Servos[PIE2].write(NEUTRAL,CLOSESPEED); // Turn Camera Lens LED Random Colors Servos[PIE2].write(NEUTRAL,CLOSESPEED); // Turn Camera Lens LED Random Colors Servos[TIE1].write(NEUTRAL,CLOSESPEED);				
						colorWipe(basicColors[random(1,10]], 255); // Turn Camera Lens LED Random Colors Servos[MED1].write(NEUTRAL,CLOSESPEED,true); //wait Servos[LTL2].write(NEUTRAL,CLOSESPEED); colorWipe(basicColors[random(1,10]], 255); // Turn Camera Lens LED Random Colors Servos[LTG1].write(NEUTRAL,CLOSESPEED,true); //wait Servos[LTL3].write(NEUTRAL,CLOSESPEED); colorWipe(basicColors[random(1,10]], 255); // Turn Camera Lens LED Random Colors Servos[MED2].write(NEUTRAL,CLOSESPEED,true); //wait // Detach from the Pies Servos[LTL1].detach(); Servos[LTL1].detach();				
						Servos[LTL3].detach(); Servos[MED1].detach(); Servos[MED2].detach(); Servos[PiE1].detach(); Servos[PiE1].detach(); Servos[PiE2].detach(); Servos[PiE3].detach(); Servos[PiE3].detach(); Servos[PiE4].detach(); Servos[PiE4].detach(); Serial.println("Closed"); colorWipe(C_BLUE, 255); // Turn Camera Lens LED Blue } else { // Open Pie Panels				
						Serial.println("Opening"); panelsOpen=true; colorWipe(C_GREEN, 255); // Turn Camera Lens LED Green // Attach to all the panel so we can move them Servos[LTL1].attach(LITTLE_PANEL_1_OF_3); Servos[LTL2].attach(LITTLE_PANEL_2_OF_3); Servos[LTL3].attach(LITTLE_PANEL_3_OF_3); Servos[MED1].attach(MED_PANEL_1_OF_2); Servos[MED1].attach(MED_PANEL_1_OF_2); Servos[MED2].attach(MED_PANEL_2_OF_2); Servos[NED1].attach(PIE1_SERVO_PIN); Servos[PIE1].attach(PIE1_SERVO_PIN); Servos[PIE3].attach(PIE3_SERVO_PIN); Servos[PIE3].attach(PIE3_SERVO_PIN);				
						Servos[PIE4].attach(PIE4_SERVO_PIN); // Open them all at once. Servos[LTL1].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[LTL2].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[MED1].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[MED1].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[MED2].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[LRG1].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[PIE1].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[PIE2].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[PIE3].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[PIE3].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[PIE3].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED); Servos[PIE4].write(NEUTRAL-PIE_ADD_DEGREES,OPENSPEED);				
						// Detach from the Pies Servos[LTL1].detach(); Servos[LTL2].detach(); Servos[LTL3].detach(); Servos[MED1].detach(); Servos[MED2].detach(); Servos[MED1].detach(); Servos[PiE3].detach(); Servos[PiE3].detach(); Servos[PiE3].detach(); Servos[PiE3].detach(); Servos[PiE3].detach(); Servos[PiE3].detach();				
						Serial.println("Opened"); } i2cCommand=-1; // always reset i2cCommand to -1, so we don't repeatedly do the same command //digitalWrite(STATUS_LED, LOW); }				

Back to Quick Refe	rence Tab Gesture	Stealth Config.txt	Body Servo Expander I2C = 9	Body Arduino Pro Mini I2C = 8	Body Arduino Mega I2C = 7	Dome Expander I2C = 10	Flthy HP 12C = 25	HP Servo Board I2C = 65	Teeces (Serial)	Teeces (Serial)
Quick Wave 1 – Opens the Dome 2 – Changes the Camaera Lens LED Colors to a random color each time it closes a few panels 3 – Sets the HP's to random pulse	Left, Left	g=454,4,10,8				case 8: quickWave(); break; void Wave1() { sendFlthyl2Ccmd("A007"); Serial.println("Wave Panels 1");	Turn all HPs to Rainbow			
						// Attach to all the panel so we can move them Servos[LTL1].attach(LITTLE_PANEL_1_OF_3); Servos[LTL2].attach(LITTLE_PANEL_2_OF_3); Servos[MED1].attach(LITTLE_PANEL_3_OF_3); Servos[MED2].attach(MED_PANEL_1_OF_2); Servos[MED2].attach(MED_PANEL_2_OF_2); Servos[MED2].attach(LARGE_PANEL); Servos[PIE2].attach(PIE1_SERVO_PIN); Servos[PIE2].attach(PIE3_SERVO_PIN); Servos[PIE3].attach(PIE3_SERVO_PIN); Servos[PIE4].attach(PIE4_SERVO_PIN); Servos[PIE4].attach(PIE4_SERVO_PIN); //Move the Servos to Nuetral position Servos[LTL1].write(NEUTRAL,150);				
						//Move the Servos to Nuetral position Servos[LTL1].write(NEUTRAL,150); Servos[LTL2].write(NEUTRAL,150); Servos[LTL3].write(NEUTRAL,150); Servos[MED1].write(NEUTRAL,150); Servos[MED2].write(NEUTRAL,150); Servos[LRG1].write(NEUTRAL,150); Servos[PIE1].write(NEUTRAL,150); Servos[PIE2].write(NEUTRAL,150); Servos[PIE3].write(NEUTRAL,150); Servos[PIE3].write(NEUTRAL,150); Servos[PIE3].write(NEUTRAL,150); Servos[PIE4].write(NEUTRAL,150);				
						for (int i=0; i<4; i++) { //RUN THIS 4 TIMES Serial.println("Wave"); colorWipe(basicColors[random(0,10]], 255); // Turn Camera Lens LED Random Colors Servos[LTL1].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[LTL2].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[LTL3].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[MED1].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[MED2].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); Servos[MED2].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED);				
						delay(WAVEDELAY); Servos[LRG1].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[PIE1].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[PIE2].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[PIE3].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[PIE3].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY); Servos[PIE4].write(NEUTRAL-PIE_ADD_DEGREES,WAVESPEED); delay(WAVEDELAY *2.5); Servos[LTL1].write(NEUTRAL,WAVESPEED);				
						delay(WAVEDELAY); Servos[LTL2].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY); Servos[LTL3].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY); Servos[MED1].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY); Servos[MED2].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY); Servos[MED2].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY); Servos[LRG1].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY); Servos[PIE4].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY);				
						Servos[PIE3].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY); Servos[PIE2].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY); Servos[PIE1].write(NEUTRAL,WAVESPEED); delay(WAVEDELAY * 2); } // Disconnect from our servos Servos[LT11].detach(); Servos[LT12].detach(); Servos[LT13].detach();				
						Servos[MED1].detach(); Servos[MED2].detach(); Servos[MED2].detach(); Servos[PIE1].detach(); Servos[PIE3].detach(); Servos[PIE3].detach(); Servos[PIE4].detach(); Servos[PIE4].detach(); colorWipe(C_BLUE, 255); // Turn Camera Lens LED Blue sendFithyl2Ccmd("A00354"); Serial.println("Wave Done");	Turn all HPs to pulse blue and speed of 4			
						i2cCommand=-1; // always reset i2cCommand to -1, so we don't repeatedly do the same command //digitalWrite(STATUS_LED, LOW); }				