Gyroscope Stabilization

* Variables
  + gyroZeroPitch – pitch stable point
  + gyroZeroRoll – roll stable point
  + gyroZeroYaw – yaw stable point
* Loop *val* from 0 to 30  
  + Get roll, pitch, yaw from IMU via I2C
    - newRoll, newPitch, newYaw retrieved
  + if val >= 10  
    - Sum the values
      * gyroZeroPitch += newPitch
      * gyroZeroRoll += newRoll
      * gyroZeroYaw += newYaw
  + *end* IF
* *end* Loop
* Divide by number of total values
  + gyroZeroPitch = gyroZeroPitch / 20;
  + gyroZeroRoll = gyroZeroRoll / 20;
  + gyroZeroYaw = gyroZeroYaw / 20;