

Morpho-Motion communication protocol

Meta Data												Actual Data																			
#	!	Message_ID	!	%	Message_Type	%	&	Address	&	[Time]	*	<	Data_1-Field_1	/	Data_1-Field_2	>	<	Data_2-Field_1	/	Data_2-Field_2	>	⋮	<	Data_n-Field_1	/	Data_n-Field_2	>	*	\$

- Message_ID: A unique ID for each message sent out either from the PC or Skymega. [Unsigned long]
- Message_Type:
 - 0: Command to move servo motor to a specific angle mentioned [PC to Skymega].
 - 1: Requesting current servo position [PC to Skymega].
 - 2: Message containing servo position data with time read at [Skymega to PC].
 - 3: Requesting time [PC to Skymega].
 - 4: Message containing current time [Skymega to PC].
 - 5: Requesting Broadcast_On.
 - 6: Requesting Broadcast_Off.
- Address:
 - 0: Servo 1
 - 1: Servo 2
 - 2: Servo 3
 - 3: Servo 4
 - 4: All servos
- ~~Time: Contains the time [in milliseconds] at which the servo position(s) mentioned in the message frame was/were read at. [Unsigned long].~~
- Time: Contains the time [in milliseconds] at which the message frame was constructed. [Unsigned long].
- Data: Contains the actual data [Servo angle to be actuated with or current servo position]
 - Field_1: Raw servo position data. [Signed long]
 - ~~Field_2: Number of values after the decimal point, data in *Field_1* contains. [Unsigned int]~~
~~Processed data = Field_1/10^Field_2.~~
 - Field_2: Signed time difference between value in field *Time* and the time at which the respective Servo's POT data was read. [Signed long]