

MAIN					
M	Calibration Mode	MODE SWITCH	!	Debug 0	SET DEBUG MASK (0-3)
&	FS Browser Mode		@	Debug 1	
*	OTA Mode		#	Debug 2	
h	HARDWARE INFO DUMP		\$	Debug 3	
Robot Control					
w	PITCH++	MANUAL CONTROL	=	STEP - DECREASE	ROUTINE CONTROL - MOVEMENT
s	PITCH--		-	STEP - INCREASE	
a	ROLL--		[STEP XY DECREASE	
d	ROLL++]	STEP XY INCREASE	
E	YAW++10		;	STEP Z DECREASE	
Q	YAW--10		\	STEP Z INCREASE	
Z	HEIGHT DECREASE		,	OFFSET DECREASE	
C	HEIGHT INCREASE		.	OFFSET INCREASE	
SPACE	STAND BUTTON	ROUTINE CONTROL	p	PRPORTIONAL (P) DECREASE	GYRO CONTROL (PROC)
1	WALK - Toggle		P	PROPORTIONAL (P) - INCREASE	
2	GAIT - Toggle		i	INTEGRAL (I) - DECREASE	
3	BALANCE - Toggle		I	INEGRAL (I) - INCREASE	
4	Toggle BTN FLASH		o	DERIVATIVE (D) - DECREASE	
9	SAVE USER DATA	saves user date for STEPS. Commandhalndle r.cpp	O	DERIVATIVE (D) - INCREASE	
0	LOAD USER DATA	loads user data for STEPS. Commandhalndle r.cpp	u	PID TOGGLE	
			U	Calibrate	
Calibration					
1	LEG SELECTION		=	Nothing?	_calAngles[BODY_NUM_LEGS]
2			+	Calibrate: +.05 degrees on selected leg/joint	
3			-	Calibrate: -.05 degrees on selected leg/joint	
4]	Calibrate: +.05 degrees on selected leg/joint	
5	Camera pan/tilt config		[Calibrate: -.05 degrees on selected leg/joint	_cfgServos[BODY_NUM_LEGS]
6	Nothing?				
7	JOINT SELECTION (ON SELECTED LEG)		q	IDLE POSE (ALL 0 degree)	POSE FOR CALIBRATION
8			w	READY POSE !	
9			e	STRAIGHT POSE !	
			c	CLEAR CALIBRATION	SAVE/LOAD CALIBRATION FOR SERVOS
			s	SAVE CALIBRATION	
			l	LOAD CALIBRATION	
			p	PRINT CALIBRATION INFO	