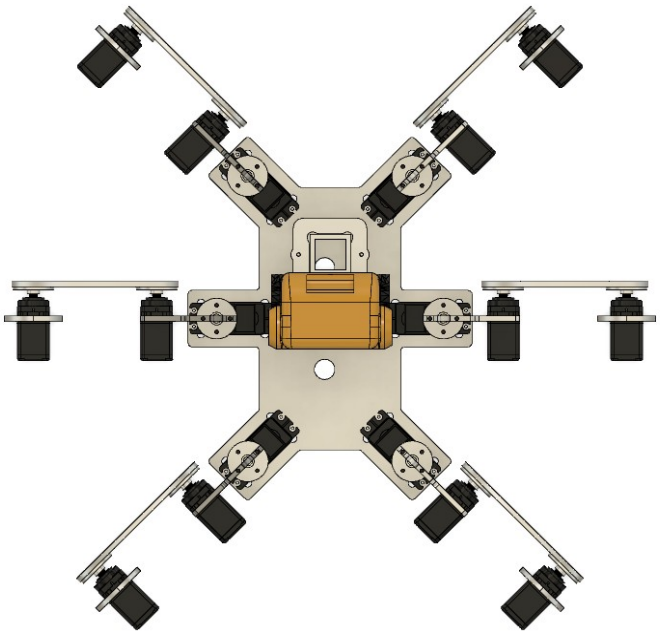
legHomePositions

Leg joint home positions							
Leg number	**Side**	**Position**	**Port**	**Joint**	**Andrew Home value**	**Doug Home Value**	**Servo Number**
1	Right=0	Front	0	Hip	293	313	0
1	Right	Front	1	Knee	283	300	1
1	Right	Front	2	Ankle	294	310	2
2	Right	Middle	3	Hip	300	310	3
2	Right	Middle	4	Knee	279	307	4
2	Right	Middle	5	Ankle	275	285	5
3	Right	Back	6	Hip	290	292	6
3	Right	Back	7	Knee	275	305	7
3	Right	Back	8	Ankle	275	310	8
4	Left=1	Front	0	Hip	290	295	9
4	Left	Front	1	Knee	302	298	10
4	Left	Front	2	Ankle	306	285	11
5	Left	Middle	3	Hip	306	288	12
5	Left	Middle	4	Knee	299	290	13
5	Left	Middle	5	Ankle	295	290	14
6	Left	Back	6	Hip	286	295	15
6	Left	Back	7	Knee	312	305	16
6	Left	Back	8	Ankle	316	310	17

Motor controller I2C addressing		
Side	**A0 Status**	**I2C Address**
Left	CLOSE	0x41
Right	OPEN	0x40

To tune use MQTT command:
stp,<side>,<port>,<pwm>

Side = 0 (right), 1 (left)
Port = 0-8
PWM = ~300+/-



Leg joint home positions							
Leg number	**Side**	**Position**	**Port**	**Joint**	**Andrew Home value**	**Doug Home Value**	**Servo Number**
1	Right=0	Front	0	Hip	310	313	0
1	Right	Front	1	Knee	302	300	1
1	Right	Front	2	Ankle	302	310	2
2	Right	Middle	3	Hip	290	310	3
2	Right	Middle	4	Knee	290	307	4
2	Right	Middle	5	Ankle	286	285	5
3	Right	Back	6	Hip	283	292	6
3	Right	Back	7	Knee	289	305	7
3	Right	Back	8	Ankle	297	310	8
4	Left=1	Front	0	Hip	309	295	9
4	Left	Front	1	Knee	297	298	10
4	Left	Front	2	Ankle	310	285	11
5	Left	Middle	3	Hip	300	288	12
5	Left	Middle	4	Knee	290	290	13
5	Left	Middle	5	Ankle	290	290	14
6	Left	Back	6	Hip	295	295	15
6	Left	Back	7	Knee	292	305	16
6	Left	Back	8	Ankle	289	310	17

Motor controller I2C addressing		
Side	**A0 Status**	**I2C Address**
Left	CLOSE	0x41
Right	OPEN	0x40