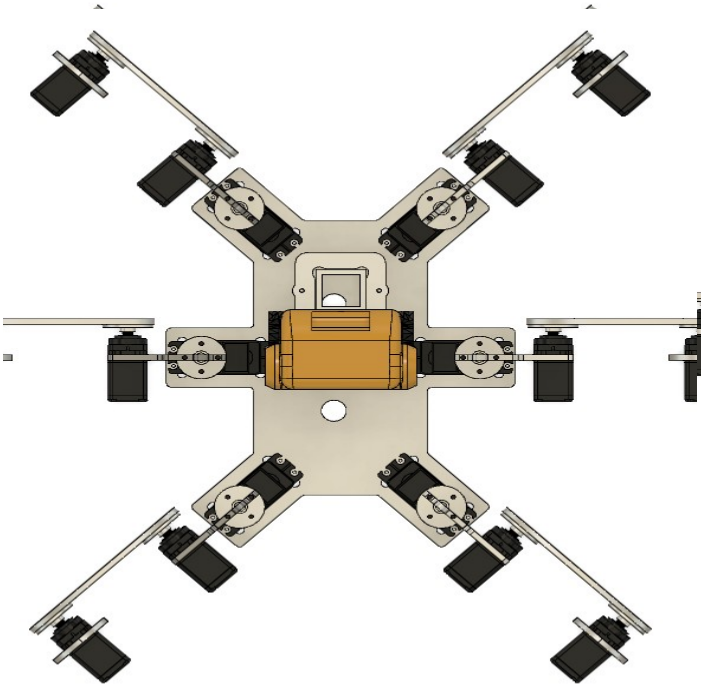
legHomePositions

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	295	0
1	Right	Front	1	Knee	283	290	1
1	Right	Front	2	Ankle	294	300	2
2	Right	Middle	3	Hip	300	304	3
2	Right	Middle	4	Knee	279	295	4
2	Right	Middle	5	Ankle	275	310	5
3	Right	Back	6	Hip	290	316	6
3	Right	Back	7	Knee	275	285	7
3	Right	Back	8	Ankle	275	307	8
4	Left=1	Front	0	Hip	290	315	9
4	Left	Front	1	Knee	302	297	10
4	Left	Front	2	Ankle	306	298	11
5	Left	Middle	3	Hip	306	310	12
5	Left	Middle	4	Knee	299	306	13
5	Left	Middle	5	Ankle	295	292	14
6	Left	Back	6	Hip	286	298	15
6	Left	Back	7	Knee	312	315	16
6	Left	Back	8	Ankle	316	293	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+/-



On the robots right side, side 0,	On the robot's left side, side 1, **exact opposite**
- increasing hip's PWM value rotates it backward	- increasing hip's PWM value rotates it forward
- increasing knee's PWM raises the ankle	- increasing knee's PWM lowers the ankle
- increasing ankle's PWM moves toe inward	- increasing ankle's PWM moves toe outward