```
    // If the data is back
    if (Serial.available() > 20) {
        // Parse the data
        xStr = Serial.readStringUntil(',');
        yStr = Serial.readStringUntil(',');
        zStr = Serial.readStringUntil('\n');
        // Convert inoto floats
        xVal = xStr.toFloat()*180/M_PI;
        yVal = yStr.toFloat()*180/M_PI;
        zVal = zStr.toFloat()*180/M_PI;

        // Turn LED on
        digitalWrite(2,LOW);

        // Pull transmit enable high
        digitalWrite(PD4,HIGH);

#ifdef LIDAR
        // Find lidar distance
        float lidarDist = lidar1.distance();
        // Send lidar data over serial
        Serial.print('D');
        Serial.print(lidarDist);
        Serial.print('I');
#endif
        // Send gyro data over serial
        Serial.print('A');
        Serial.print(xVal);
        Serial.print('E');

        // Ensure all data sent
        Serial.flush();

        // Let transmit enable fall low
        digitalWrite(PD4,LOW);
    }

}
```