

## Raspberry Pi Packet:

Start Byte	Command Byte	Data Byte	Stop Byte
0xAA	UInt8	UInt8	0x55

## Tiva Packet (Single Byte Return):

Start Byte	Return Value	Stop Byte
0xAA	uint8_t	0x55

## Tiva Packet (Global Pose Return):

Start Byte	X Byte	Y Byte	Theta Byte	Stop Byte
0xAA	uint8_t	uint8_t	uint8_t	0x55

Command Number	Command	Parameter/Return Value
0x0	Brake **Extra Command**	N/A
0x1	Drive Forward	uint8_t distance
0x2	Drive Backward	uint8_t distance
0x3	Turn Right	uint8_t radians
0x4	Turn Left	uint8_t radians
0x5	Get Bumper Status	uint8_t bumper
0x6	Get Right IR Value	uint8_t distance
0x7	Get Center IR Value	uint8_t distance
0x8	Get Left IR Value	uint8_t distance
0x9	Get Closest Object	uint8_t distance
0xA	Get Pose	uint8_t x, y, theta
0xB	Set Speed	uint8_t magnitude
0xC	Toggle Obstacle Avoidance	N/A