`Pat's 14M2 Infrared HEXAPOD Walk Program All + Annotations Version 7 - 16/7/2016

`Note- Left Leg=Pin 2,Centre Leg=Pin 1,Right Leg=Pin 3.

`Front Lights=C.0, Back Lights=C.1, Note Throw is angle movement of Servo (+ or -).

Init:

servo **2**,**165** `Centralises servo 2

servo **1**,**165** `Centralises servo 1

servo **3**,**165** `Centralises servo 3

pause **200**

main:

infrain2

if infra=**116** then Frontwards

if infra=**117** then Backwards

if infra=**51** then Right

if infra=**52** then Left

if infra=**101** then Centre

pause **200**

goto main

Centre:

servo **2**,**165** `Centralises servo 2

servo **1**,**165** `Centralises servo 1

servo **3**,**165** `Centralises servo 3

pause **200** `pauses 200 milliseconds

low C.0 `Turns Off Front Lights

low C.1 `Turns Off Back Lights

goto main `Returns

Frontwards:

high C.0 `Turns On Front Lights

servo **1**,**185** `Throw = +20,Moves servo 1, lifts centre leg, up right

pause **200** `pauses 200 milliseconds

servo **2**,**185** `Throw = +20,Moves servo 2, moves outside left legs, back

servo **3**,**185** `Throw = +20,Moves servo 3, moves outside right legs, forward

pause **200** `pauses 200 milliseconds

servo **1**, **145** `Throw = -20,Moves servo 1, moves centre leg, up left

pause **200** `pauses 200 milliseconds

servo **2**,**145** `Throw = -20,Moves servo 2, moves outside left legs, forward

servo **3**,**145** `Throw = -20,Moves servo 3, moves outside right legs, back

pause **200** `pauses 200 milliseconds

servo **2**,**165** `Centralises servo 2

servo **1**,**165** `Centralises servo 1

servo **3**,**165** `Centralises servo 3

pause **200** `pauses 200 milliseconds

goto main `Returns

Backwards:

high C.1 `Turns On Back Lights

servo **1**,**145** `Throw = -20,Moves servo 1, moves centre leg, up left

pause **200** `pauses 200 milliseconds

servo **2**,**185** `Throw = +20,Moves servo 2, moves outside left legs, back

servo **3**,**185** `Throw = +20,Moves servo 3, moves outside right legs, forward

pause **200** `pauses 200 milliseconds

servo **1**, **185** `Throw = +20,Moves servo 1, lifts centre leg, up right

pause **200** `pauses 200 milliseconds

servo **2**,**145** `Throw = -20,Moves servo 2, moves outside left legs, forward

servo **3**,**145** `Throw = -20,Moves servo 3, moves outside right legs, back

pause **200** `pauses 200 milliseconds

servo **2**,**165** `Centralises servo 2

servo **1**,**165** `Centralises servo 1

servo **3**,**165** `Centralises servo 3

pause **200** `pauses 200 milliseconds

goto main `Returns

Left:

high C.0 `Turns On Front Lights

servo **1**,**185** `Throw = +20,Moves servo 1, lifts centre leg, up right

pause **200** `pauses 200 milliseconds

servo **3**,**185** `Throw = +20,Moves servo 3, moves outside right legs, back

pause **200** `pauses 200 milliseconds

servo **1**, **145** `Throw = -20,Moves servo 1, moves centre leg, up left

pause **200** `pauses 200 milliseconds

servo **3**,**145** `Throw = -20,Moves servo 3, moves outside right legs, back

pause **200** `pauses 200 milliseconds

servo **2**,**165** `Centralises servo 2

servo **1**,**165** `Centralises servo 1

servo **3**,**165** `Centralises servo 3

pause **200** `pauses 200 milliseconds

goto main `Returns

Right:

high C.0 `Turns On Front Lights

servo **1**,**145** `Throw = -20,Moves servo 1, lifts centre leg, up right

pause **200** `pauses 200 milliseconds

servo **2**,**145** `Throw = -20,Moves servo 2, moves outside left legs, forward

pause **200** `pauses 200 milliseconds

servo **1**,**185** `Throw = +2 jk0,Moves servo 1, moves centre leg, up left

pause **200** `pauses 200 milliseconds

servo **2**,**185** `Throw = +20,Moves servo 2, moves outside left legs, back

pause **200** `pauses 200 milliseconds

servo **2**,**165** `Centralises servo 2

servo **1**,**165** `Centralises servo 1

servo **3**,**165** `Centralises servo 3

pause **200** `pauses 200 milliseconds

goto main `Returns