

## GaitPIC-Nomad Command Protocol

All serial communication is at 38400 baud.

See *GaitPIC-Demo.bsp* and *GaitPIC-Template.bsp* for more detailed examples.

### Walk Command

!w Gait Direction Speed Count FF

#### Gait

- 0 = Walk
- 1 = Spin Clockwise
- 2 = Spin Counter clockwise

#### Direction

- 0 = 0° front is between legs 0 and 6
- 1 = 60° front is between legs 0 and 2
- 2 = 120° front is between legs 2 and 3
- 3 = 180° front is between legs 3 and 4
- 4 = 240° front is between legs 4 and 5
- 5 = 300° front is between legs 5 and 6

#### Speed

- 0 = Fast
- 1 = Normal
- 2 = Slow
- 3 = Slow with high step

#### Count

- 0-253 = number of steps
- 254 = continuous

FF – end of message

**Stop Command** – Stop after current step completes

!s FF

**Home Command** – Set all legs to the home position

!h FF