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//Requesting Float data codes:
case REQ_FLOAT:
        //str_clk = 1;
        Serial.println("Going to send a float");
        //TODO: Put a float (perhaps pi) into a command response and send it.
        //str_clk = str_clk + 1;
        memcpy(res_cmd->data, &f[1], 4); //1
        memcpy(res_cmd->data+4, &f[2], 4); //2
        memcpy(res_cmd->data+8, &f[3], 4); // 3
        memcpy(res_cmd->data+12, &f[4], 4); // 4
        memcpy(res_cmd->data+16, &f[5], 4); //5
        memcpy(res_cmd->data+20, &f[6], 4); //6
        memcpy(res_cmd->data+24, &f[7], 4); // 7
        memcpy(res_cmd->data+28, &f[8], 4); //8
        memcpy(res_cmd->data+32, &f[9], 4); //9
        memcpy(res_cmd->data+36, &f[10], 4); // 10
        memcpy(res_cmd->data+40, &f[11], 4); // 11
        memcpy(res_cmd->data+44, &f[12], 4); //12
        memcpy(res_cmd->data+48, &f[13], 4); //13
        memcpy(res_cmd->data+52, &f[14], 4); // 14
        memcpy(res_cmd->data+56, &f[15], 4); //15
        memcpy(res_cmd->data+60, &f[16], 4); //16
        memcpy(res_cmd->data+64, &f[17], 4); // 17
        memcpy(res_cmd->data+68, &f[18], 4); // 18
        memcpy(res_cmd->data+72, &f[19], 4); //x odom
        memcpy(res_cmd->data+76, &f[20], 4); //y odom
        memcpy(res_cmd->data+80, &f[21], 4); //yaw
        res_cmd->command_type = GIVE_FLOAT;
        amdtpsSendData((uint8_t *)res_cmd, 86);
        break;

//receiving commands
if (availableMessage()){
      Serial.println("Bluetooth Message:");
      char *str_1 = pullMessage();
      Serial.printf("%s",str_1);
      if(strcmp(str_1, "s") == 0){
      Serial.printf("Start\n");
      str_clk = 1;}
      else if(strcmp(str_1, "c") == 0){
      Serial.printf("Scanning\n");
      scan_flag = 1; }
      else if(strcmp(str_1, "f") == 0){
      Serial.printf("Go straight\n");
      for_time = 1; }
      else if(for_time ==1){
      int test_num = atoi(str_1);
      fwd_time = test_num;
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forward_flag = 1;
for_time = 0;}
else if(strcmp(str_1, "t") == 0){
Serial.printf("turnning\n");
angle_time = 1; }
else if(angle_time == 1){
int test_num = atoi(str_1);
turn_time = test_num;
turn_90_f = 1;
angle_time = 0; }
else if(strcmp(str_1, "a") == 0){
Serial.printf("changing speed\n");
speed_flag = 1;   }
else if(speed_flag == 1){
int test_num = atoi(str_1);
motor_speed = test_num;
speed_flag = 0; }
else if(strcmp(str_1, "v") == 0){
Serial.printf("changing speed\n");
f_speed_flag = 1;   }
else if(f_speed_flag == 1){
int test_num = atoi(str_1);
f_motor_speed = test_num;
f_speed_flag = 0; }
else if(strcmp(str_1, "w") == 0){
Serial.printf("changing speed\n");
t_speed_flag = 1;   }
else if(t_speed_flag == 1){
int test_num = atoi(str_1);
t_motor_speed = test_num;
t_speed_flag = 0; }
printOverBluetooth("Message Received.");}
```