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#include
<Servo.h>

Servo gripper;
Servo wrist;
Servo elbow;
Servo shoulder;
Servo base;

double base_angle=90;
double shoulder_angle=90;
double elbow_angle=90;
double wrist_angle=90;

void setup() {
  Serial.begin(115200);
  base.attach(8);
  shoulder.attach(9);
  elbow.attach(10);
  wrist.attach(11);
  gripper.attach(12);

  base.write(base_angle);
  shoulder.write(shoulder_angle);
  elbow.write(elbow_angle);
  wrist.write(wrist_angle);
}

String getValue(String data, char separator, int index)
{
  int found = 0;
  int strIndex[] = {0, -1};
  int maxIndex = data.length()-1;

  for(int i=0; i<=maxIndex && found<=index; i++){
    if(data.charAt(i)==separator || i==maxIndex){
      found++;
      strIndex[0] = strIndex[1]+1;
      strIndex[1] = (i == maxIndex) ? i+1 : i;
    }
  }
}

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    return found>index ? data.substring(strIndex[0], strIndex[1]) :
    "";
}

void loop() {

    String computerText = Serial.readStringUntil('@');
    computerText.trim();
    if (computerText.length() == 0) {
        return;
    }
    // 92-0-130
    String command = getValue(computerText, ' ',0);

    if (command == "right" || command == "رايت" || command ==
"Right") {
        base.write(base_angle -= 20);
    }
    if (command == "left" || command == "Left" || command == "لفت")
{
        base.write(base_angle += 20);
    }

    if (command == "top" || command == "توب" || command == "Top") {
        shoulder.write(shoulder_angle -= 20);
    }

    if (command == "bottom" || command == "بوتوم" || command ==
"Bottom") {
        shoulder.write(shoulder_angle += 20);
    }
    Serial.println(command);
    Serial.println("WORKING");
    delay(1000);
}

```