**Smart Mulli Storage Car Parking**

**Source Code:**

const int stepPin1 = 5; //SLIDER EVEN

const int dirPin1 = 6;

const int enPin1 = 7;

const int stepPin2 = 23; //SLIDER ODD

const int dirPin2 = 25;

const int enPin2 = 27;

const int stepPin3 = 22; //180 ROTATE STEPPER

const int dirPin3 = 24;

const int enPin3 = 26;

const int stepPin4 = 2; //BIG MOTOR

const int dirPin4 = 3;

const int enPin4 = 4;

#include <Keypad.h>

/\*-------------------------------KEYPAD---------------------------------------\*/

const byte ROWS = 8; // Four rows

const byte COLS = 8; // columns

char keypressed;

// Define the Keymap

char keymap [ROWS][COLS] = {

{'X','2','3','A','E','I','0','Q'},

{'4','5','6','B','F','J','N','R'},

{'7','8','9','C','G','K','O','S'},

{'\*','M','#','D','H','l','P','T'},

{'U','Y','c','g','k','o','s','w'},

{'V','Z','d','h','L','p','t','x'},

{'W','a','e','i','m','q','u','y'},

{'1','b','f','j','n','r','v','z'}

};

// Connect keypad ROW0, ROW1, ROW2 and ROW3 to these Arduino pins.

byte rowPins[ROWS] = { 69, 68, 67, 66, 61, 60, 59, 58 };// Connect keypad COL0, COL1 and COL2 to these Arduino pins.

byte colPins[COLS] = { 65, 64, 63, 62, 57, 56, 55, 54};

// Create the Keypad

Keypad customKeypad = Keypad( makeKeymap(keymap), rowPins, colPins, ROWS, COLS);

void setup() {

// put your setup code here, to run once:

Serial.begin(9600);

// Sets the two pins as Outputs

pinMode(stepPin1,OUTPUT);

pinMode(dirPin1,OUTPUT);

pinMode(enPin1,OUTPUT);

digitalWrite(enPin1,LOW);

pinMode(stepPin2,OUTPUT);

pinMode(dirPin2,OUTPUT);

pinMode(enPin2,OUTPUT);

digitalWrite(enPin2,LOW);

pinMode(stepPin3,OUTPUT);

pinMode(dirPin3,OUTPUT);

pinMode(enPin3,OUTPUT);

digitalWrite(enPin3,LOW);

pinMode(stepPin4,OUTPUT);

pinMode(dirPin4,OUTPUT);

pinMode(enPin4,OUTPUT);

digitalWrite(enPin4,LOW);

}

void loop() {

keypressed = customKeypad.getKey(); //Read pressed keys

if ( keypressed == 'z' )

{

park1();

}

if ( keypressed == 'y' )

{

park2();

}

if ( keypressed == 'x' )

{

park3();

}

if ( keypressed == 'w' )

{

park4();

}

if ( keypressed == 'v' )

{

park5();

}

if ( keypressed == 'u' )

{

park6();

}

if ( keypressed == 't' )

{

park7();

}

if ( keypressed == 's' )

{

park8();

}

if ( keypressed == 'r' )

{

park9();

}

if ( keypressed == 'q' )

{

park10();

}

if ( keypressed == 'p' )

{

park11();

}

if ( keypressed == 'o' )

{

park12();

}

if ( keypressed == 'n' )

{

park13();

}

if ( keypressed == 'm' )

{

park14();

}

if ( keypressed == 'L' )

{

park15();

}

if ( keypressed == 'k' )

{

park16();

}

///////////////////////////////////GET COMMAND/////////////////////////////

if ( keypressed == 'D' )

{

get1();

}

if ( keypressed == 'C' )

{

get2();

}

if ( keypressed == 'B' )

{

get3();

}

if ( keypressed == 'A' )

{

get4();

}

if ( keypressed == '#' )

{

get5();

}

if ( keypressed == '9' )

{

get6();

}

if ( keypressed == '6' )

{

get7();

}

if ( keypressed == '3' )

{

get8();

}

if ( keypressed == 'M' )

{

get9();

}

if ( keypressed == '8' )

{

get10();

}

if ( keypressed == '5' )

{

get11();

}

if ( keypressed == '2' )

{

get12();

}

if ( keypressed == '\*' )

{

get13();

}

if ( keypressed == '7' )

{

get14();

}

if ( keypressed == '4' )

{

get15();

}

if ( keypressed == 'X' )

{

get16();

}

}

void park1()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park2()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park3()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park4()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park5()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park6()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 21000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park7()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park8()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park9()

{

}

void park10()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 23000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(100);

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 21000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(100);

digitalWrite(dirPin4,HIGH); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

}

void park11()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park12()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park13()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park14()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park15()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void park16()

{

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 9000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get1()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get2()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get3()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get4()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get5()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get6()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 21000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 23000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get7()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get8()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get9()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get10()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 20000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(100);

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 12000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 23000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get11()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get12()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get13()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get14()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get15()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin1,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin1,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin1,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin1,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}

void get16()

{

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 9300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//slide in

digitalWrite(dirPin2,LOW); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Upore utho

digitalWrite(dirPin4,LOW); //Changes the rotations direction

// Makes 400 pulses for making two full cycle rotation

for(int x = 0; x < 2000; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000);

//Slide out

digitalWrite(dirPin2,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 700; x++) {

digitalWrite(stepPin2,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin2,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

//Ekdom nice namo

digitalWrite(dirPin4,HIGH); // Enables the motor to move in a particular direction

// Makes 200 pulses for making one full cycle rotation

for(int x = 0; x < 11300; x++) {

digitalWrite(stepPin4,HIGH);

delayMicroseconds(500);

digitalWrite(stepPin4,LOW);

delayMicroseconds(500);

}

delay(1000); // One second delay

}