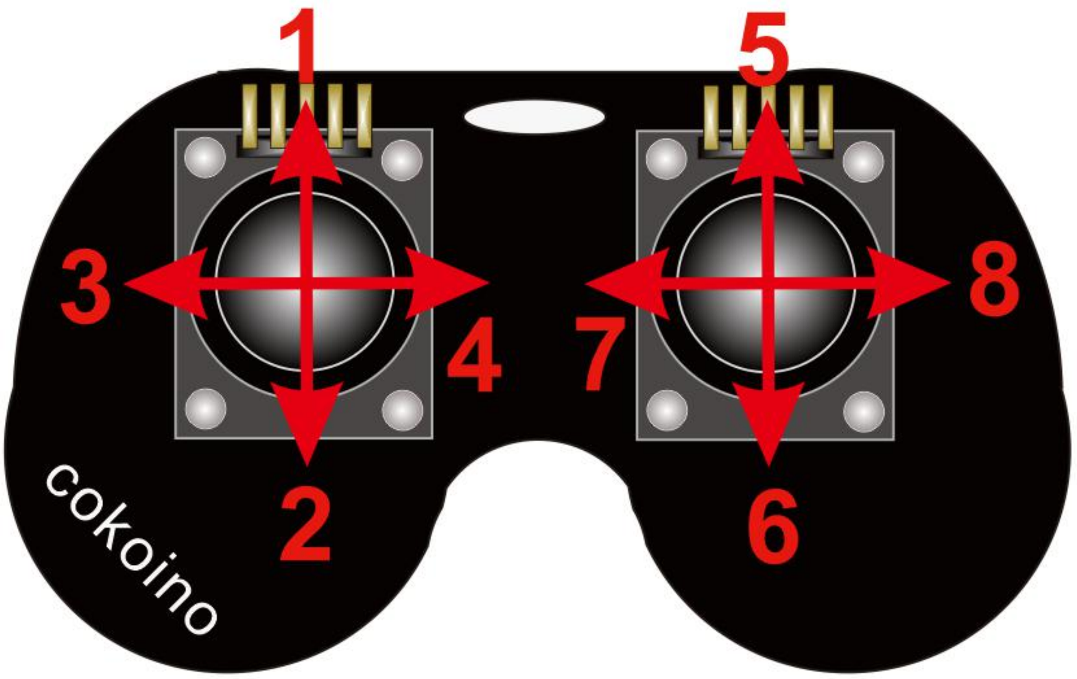
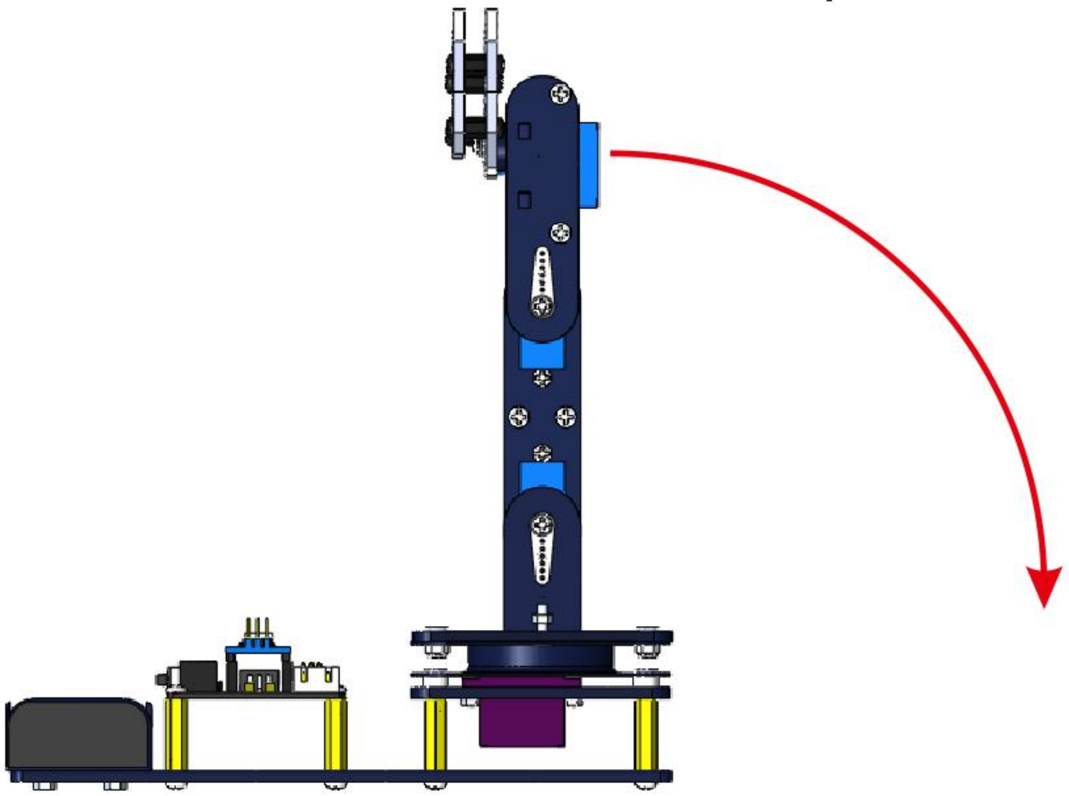
Use the joystick controller to control the robot arm

Instructions for the use of joystick controller

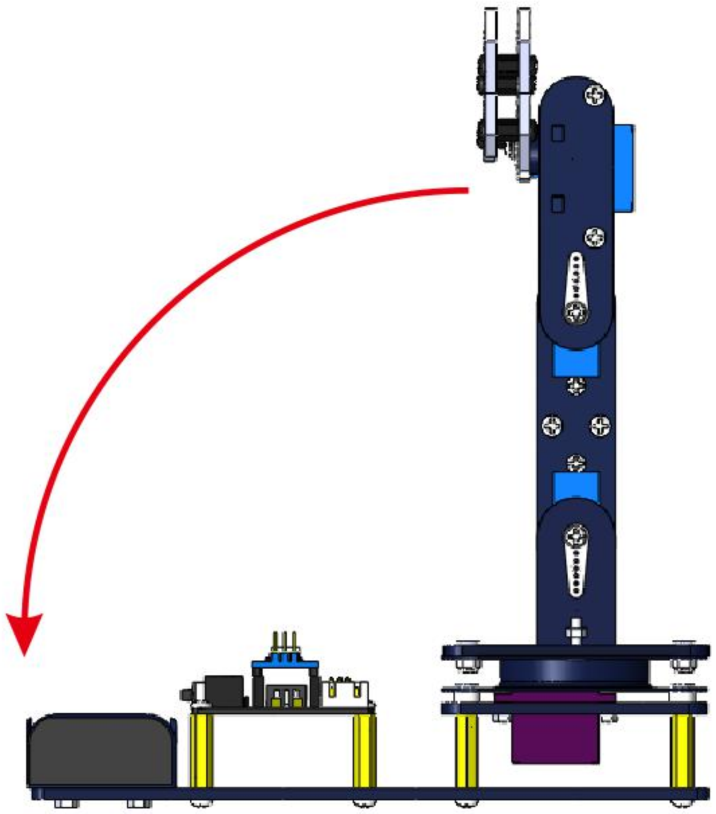
The direction of the left and right joysticks is represented by the numbers 1-8.



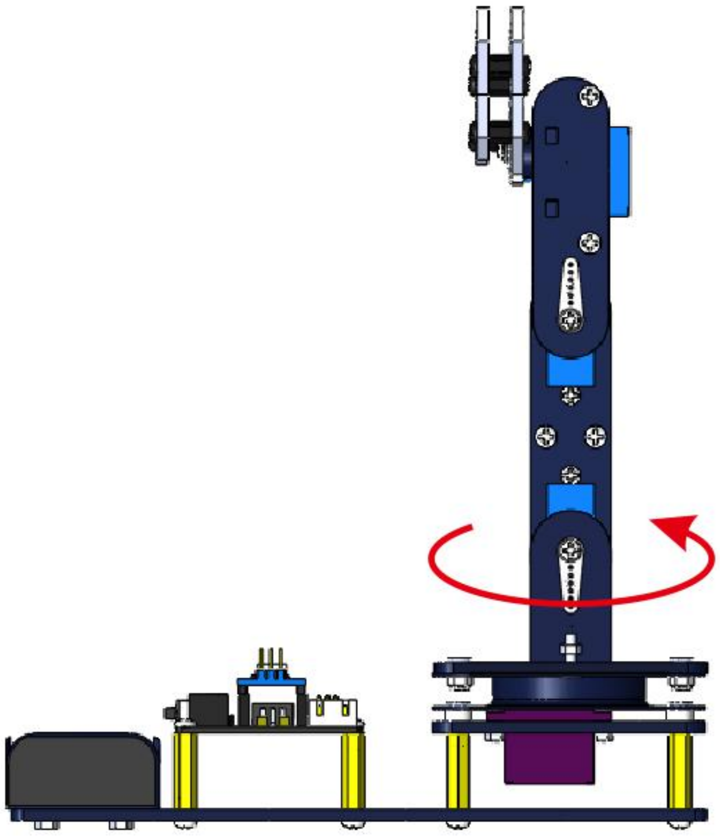
1. When the left joystick module is pushed in the 1 direction, the robot arm extended forward.



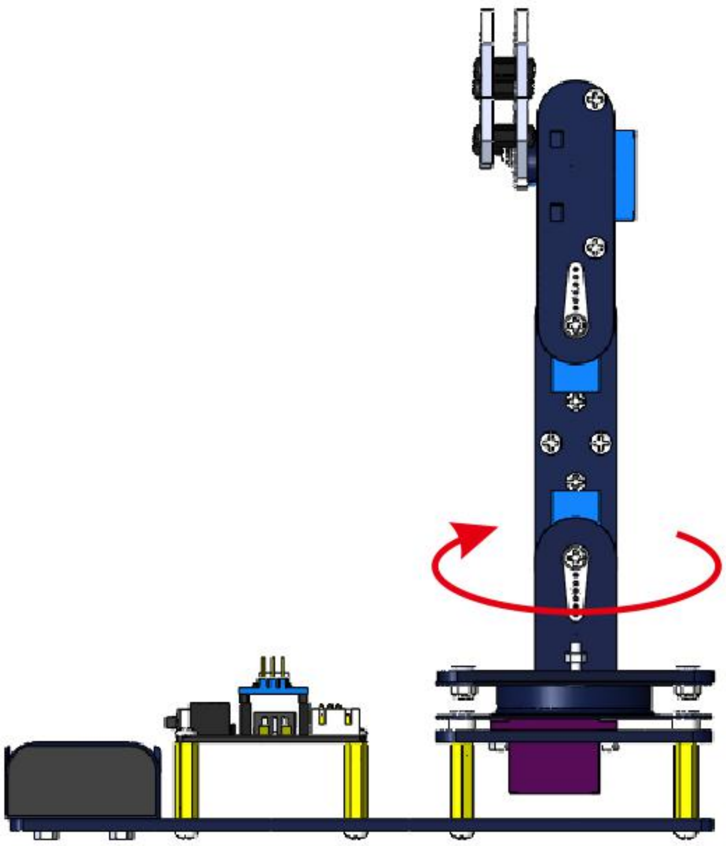
2. When the left joystick module is pushed in the 2 direction, the robot arm extended backward.



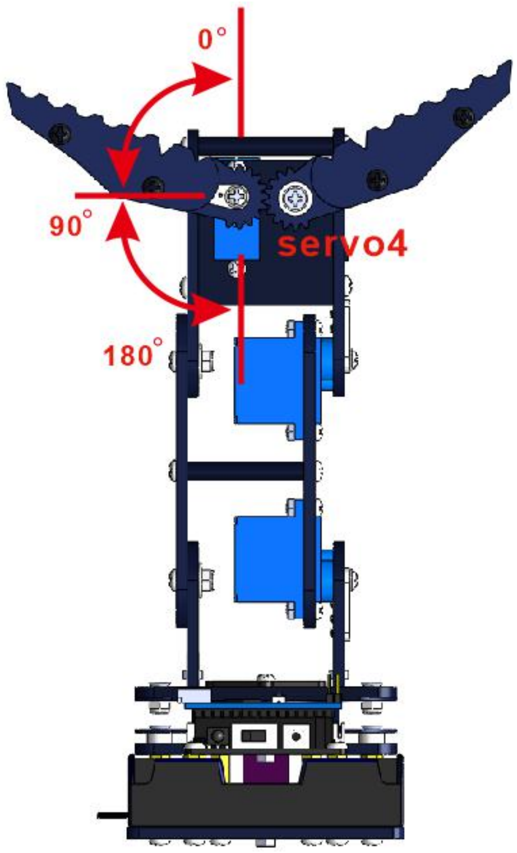
3. When the left joystick module is pushed in the 3 direction, the robot arm turn left.



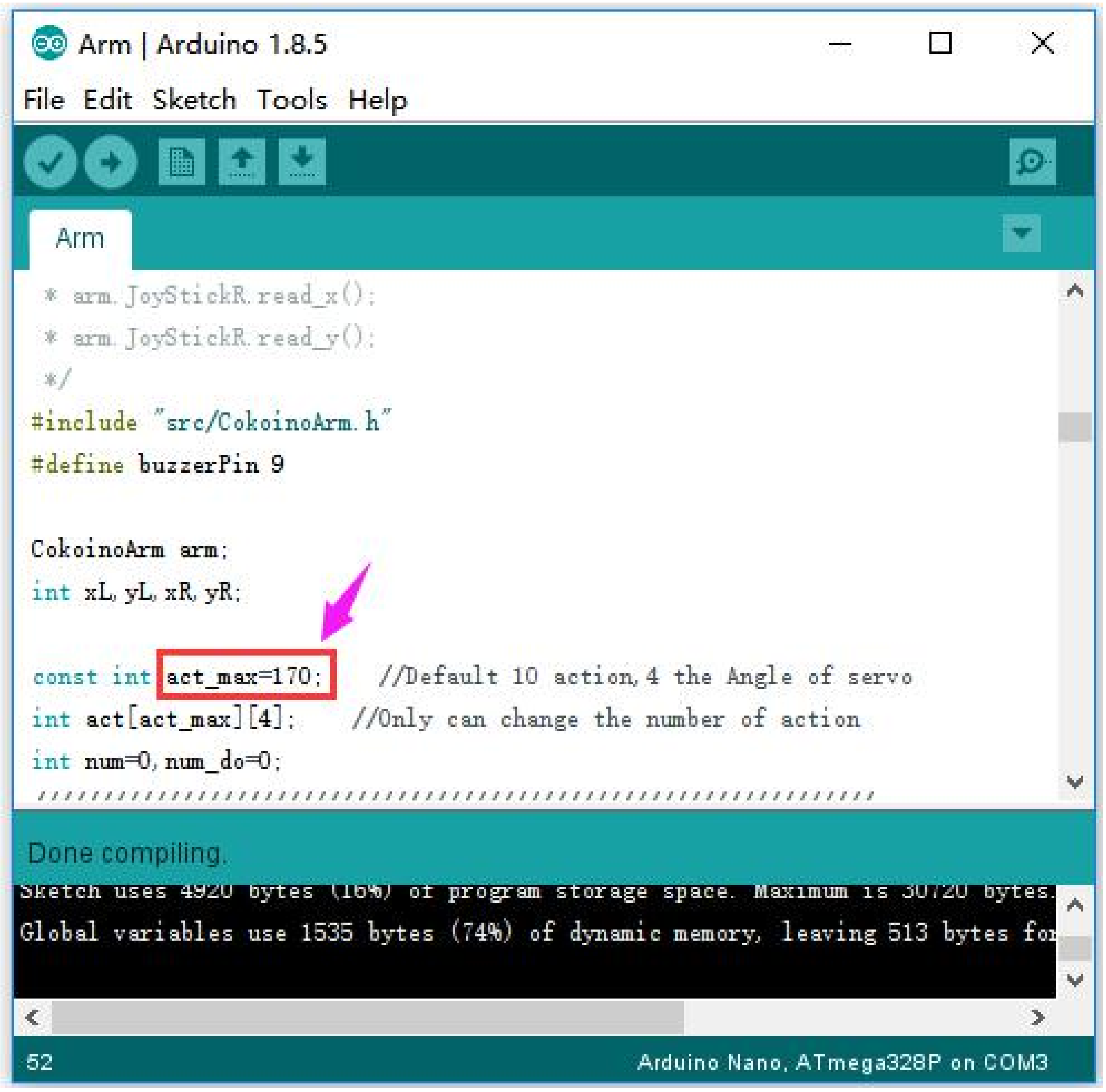
4. When the left joystick module is pushed in the 4 direction, the robot arm turn right.



5：When the right joystick module is pushed in the 5 direction, the hand of the robot arm will close(servo4 goes to 0 degree).When the right joystick module is pushed in the 6 direction, the hand of the robot arm will open (servo4 goes to 180 degree)



6: When the right joystick module is pushed in the 7 direction, the robot's nano control board record its last movement,The default program can record 10 actions continuously, and the buzzer will sound when the recorded actions are more than 10. But by modifying the numbers in the original code, the number of recorded actions can be changed, and a maximum of 170 actions can be recorded, as shown below:



```
 * arm.JoyStickR.read_x();
 * arm.JoyStickR.read_y();
 */
#include "src/CokoinoArm.h"
#define buzzerPin 9

CokoinoArm arm;
int xL,yL,xR,yR;

const int act_max=170;    //Default 10 action,4 the Angle of servo
int act[act_max][4];    //Only can change the number of action
int num=0,num_do=0;
///////////////////////////////////////////////////////////////
```

```
Sketch uses 4920 bytes (16%) of program storage space. Maximum is 30720 bytes.
Global variables use 1535 bytes (74%) of dynamic memory, leaving 513 bytes for
```

7：Perform recorded actions

When the right joystick module is pushed in the 8 direction, the buzzer beeps first, and then performs the robotic arm movements recorded on the motherboard in sequence. When performing the recorded movements, the robotic arm is not controllable. After the recorded movements are completed, the buzzer will sound a long beep again to remind the completion of the recording action.

End!