#include <Servo.h>

//initializing parameter type servo to control each

Servo motor1;

Servo motor2;

//Length of first part in cm

float length1 =6;

//Length of second part in cm

float length2 = 5;

//First angle in degree

float a1 = 180;

//First angle in rad

float a1rad = (a1/180)\*3.14;

//Second angle in degree

float a2 = 360;

//second angle in rad

float a2rad = (a2/180)\*3.14;

float x, y, at;

void setup()

{

Serial.begin(9600);

//defining where each servo attaches to

motor1.attach(10);

motor2.attach(11);

}

void loop()

{

if (a1 != 0 ){

motor1.write(a1);

motor2.write(10);

motor2.write(a2);

motor1.write(10);

x = length1\*cos(a1) + length2\*cos(a1+a2);

y = length1\*sin(a1) + length2\*sin(a1+a2);

}

delay(1000);

}