**Code of the project**

#include <VarSpeedServo.h>

#include<SoftwareSerial.h>

VarSpeedServo servo1;

VarSpeedServo servo2;

VarSpeedServo servo3;

VarSpeedServo servo4;

const int servo1Pin = 3;

const int servo2Pin = 5;

const int servo3Pin = 6;

const int servo4Pin = 9;

int bluetoothTx = 10;

int bluetoothRx = 11;

SoftwareSerial bluetooth(bluetoothTx, bluetoothRx);

void setup() {

servo1.attach(servo1Pin);

servo2.attach(servo2Pin);

servo3.attach(servo3Pin);

servo4.attach(servo4Pin);

Serial.begin(9600);

bluetooth.begin(9600);

delay(2000);

}

void loop() {

if(bluetooth.available()>0)

{

int command = bluetooth.read();

Serial.println(command);

if(command == 0)

{

servo1.write(25, 10, true);

delay(500);

servo2.write(110, 10, true);

delay(500);

servo3.write(35, 10, true);

delay(500);

servo4.write(100, 10, true);

delay(1000);

servo4.write(75, 10, true);

delay(500);

servo1.write(120, 10, true);

delay(20);

servo3.write(125, 10, true);

delay(20);

servo2.write(120, 10, true);

delay(1000);

}

else if(command == 1)

{

servo1.write(90, 20, true);

servo2.write(90, 20, true);

servo3.write(90, 20, true);

servo4.write(90, 20, true);

delay(5000);

}

else if (command == 2)

{

servo1.write(25, 10, true);

delay(500);

servo2.write(75, 10, true);

delay(500);

servo3.write(50, 10, true);

delay(500);

servo4.write(115, 10, true);

delay(1000);

servo2.write(105, 10, true);

delay(500);

servo3.write(45, 10, true);

delay(500);

servo4.write(75, 10, true);

delay(500);

servo1.write(120, 10, true);

delay(20);

servo3.write(125, 10, true);

delay(20);

servo2.write(120, 10, true);

delay(1000);

}

}

}