#include<Servo.h>

int pos1 = 1;

int pos2 = 0;

int pos3 = 1;

int directionState = 0;

const int basePin = 4;

const int upDownPin = 3;

const int landscapePin = 2;

const int baseServo = 11;

const int upDownServo = 10;

const int landscapeServo = 9;

Servo servo1;

Servo servo2;

Servo servo3;

void setup() {

pinMode(landscapePin, INPUT);

pinMode(upDownPin, INPUT);

pinMode(basePin, INPUT);

servo1.attach(landscapeServo);

servo2.attach(upDownServo);

servo3.attach(baseServo);

Serial.begin(9600);

}

void landscape(){

if(pos1 == 1){

pos1 += 90;

servo1.write(pos1);

Serial.println("landscape");

} else {

pos1 -= 90;

servo1.write(pos1);

Serial.println("profile");

}

}

void updown(){

while(pos2 < 175){

if(digitalRead(upDownPin) == HIGH){

Serial.println("up");

servo2.write(pos2);

delay(15);

pos2++;

} else {

return;

}

}

while(pos2 > 5){

if(digitalRead(upDownPin) == HIGH){

Serial.println("down");

servo2.write(pos2);

delay(15);

pos2--;

} else {

return;

}

}

}

void base(){

if(pos3 == 1){

pos3 += 178;

servo3.write(pos3);

Serial.println("start");

} else {

pos3 -= 178;

servo3.write(pos3);

Serial.println("finish");

}

}

void loop() {

if(digitalRead(landscapePin) == HIGH){

delay(250);

Serial.println("land");

landscape();

return;

}

if(digitalRead(basePin) == HIGH){

delay(250);

Serial.println("base");

base();

return;

}

if(digitalRead(upDownPin) == HIGH){

delay(250);

Serial.println("updown");

updown();

return;

}

}