#include <Servo.h>

Servo myservo1;

Servo myservo2;

Servo myservo3;

Servo myservo4;

Servo myservo5;

Servo myservo6;

#define r1 2

#define g1 3

#define r2 4

#define g2 5

#define r3 6

#define g3 7

int pos = 0;

void setup()

{

Serial.begin(9600);

pinMode(r1, OUTPUT);

pinMode(g1, OUTPUT);

pinMode(r2, OUTPUT);

pinMode(g2, OUTPUT);

pinMode(r3, OUTPUT);

pinMode(g3, OUTPUT);

digitalWrite(r1, LOW);

digitalWrite(g1, LOW);

digitalWrite(r2, LOW);

digitalWrite(g2, LOW);

digitalWrite(r3, LOW);

digitalWrite(g3, LOW);

myservo1.attach(8);

myservo2.attach(9);

myservo3.attach(10);

myservo4.attach(11);

myservo5.attach(12);

myservo6.attach(13);

delay(50);

digitalWrite(r1, HIGH);

digitalWrite(r2, HIGH);

digitalWrite(r3, HIGH);

delay(1000);

}

void loop()

{

digitalWrite(r2, LOW);

digitalWrite(r3, LOW);

digitalWrite(g2, HIGH);

digitalWrite(g3, HIGH);

for (pos =50; pos >=0; pos -= 1)

{ // goes from 0 degrees to 90 degrees

// in steps of 1 degree

myservo3.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 50; pos >=0; pos -= 1)

{ // goes from 0 degrees to 90 degrees

// in steps of 1 degree

myservo4.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo1.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo2.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo5.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo6.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

delay(5000);

digitalWrite(g2, LOW);

digitalWrite(g3, LOW);

digitalWrite(r2, HIGH);

digitalWrite(r3, HIGH);

delay(1000);

digitalWrite(r1, LOW);

digitalWrite(g1, HIGH);

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo5.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo4.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo1.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 50; pos >= 0; pos -= 1)

{ // goes from 0 degrees to 90 degrees

// in steps of 1 degree

myservo2.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 50; pos >= 0; pos -= 1)

{ // goes from 0 degrees to 90 degrees

// in steps of 1 degree

myservo3.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 50; pos >= 0; pos -= 1)

{ // goes from 0 degrees to 90 degrees

// in steps of 1 degree

myservo6.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

delay(5000);

digitalWrite(g1, LOW);

digitalWrite(r1, HIGH);

delay(1000);

digitalWrite(r3, LOW);

digitalWrite(r2, LOW);

digitalWrite(g3, HIGH);

digitalWrite(g2, HIGH);

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo2.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo3.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 0; pos <= 50; pos += 1)

{ // goes from 90 degrees to 0 degrees

myservo6.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 50; pos >= 0; pos -= 1)

{ // goes from 0 degrees to 90 degrees

// in steps of 1 degree myservo5.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 50; pos >= 0; pos -= 1)

{ // goes from 0 degrees to 90 degrees

// in steps of 1 degree myservo4.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

for (pos = 50; pos >= 0; pos -= 1)

{ // goes from 0 degrees to 90 degrees

// in steps of 1 degree

myservo1.write(pos); // tell servo to go to position in variable 'pos'

delay(15);

}

delay(5000); }