Launcher Algorithm

1) Bluetooth receiver- receives go signal with angle of rotation
2) Move the stepper motor according to given rotation
    1) Provide gear ratio to change any time (for eg. if we want to change gear ratio from 3:1 To 5:1 define a variable which act as a multiplier for stepper motor)
    2) Rotation receive is overall angle, not angle of rotation of stepper motor (for eg. if gear ratio is 3:1 and stepper is off 200 steps and angle received from bluetooth is 30 degree which means steps for stepper is 30 x {steps(i.e. 200)/360} x gear ratio multiplier(i.e. 3))
    3) Also provide variable to change steps of stepper along with gear ratio variable.
3) Give enough delay to complete rotation then send back bluetooth transmitter to prompt msg once rotation done.

Emergency algorithm: Add emergency stop over main algorithm using while loop
1) Check for emergency stop algorithm from bluetooth receiver.
2) Receives emergency stop signal from bluetooth
3) Assign a variable called flag (for while loop) to 1 from 0
4) While loop condition satisfy and proceed to next procedure.
5) Stop rotating stepper
6) Wait for 3 second
7) Return back to start position
8) Send back msg prompt through transmitter as system is "SYSTEM RESET"
9) Turn flag to 0 and wait for next emergency stop