**Test Case – Joystick Activity:**

Case 1: Left joystick

Purpose: To get the values for the servo 1 and servo 2 to get the movement of the robotic arm.

Precondition/Steps: The users input of touching the left joystick.

Expected result: When a user touches the left circle joystick, a smaller circle that tracks where the user is touching on the joystick along with giving the correct X (servo1) and Y (servo2) coordinate on the top left text field.

Case 2: Right joystick

Purpose: To get the values for the servo 3 and servo 4 to get the movement of the robotic arm.

Precondition/Steps: The users input of touching the right circle joystick.

Expected result: When a user touches the right circle joystick, a smaller circle that tracks where the user is touching on the joystick along with giving the correct X (servo3) and Y (servo4) coordinate on the top left text field.

Case 3: Claw switch

Purpose: To open and close the claw on the robotic arm

Precondition/Steps: The users input of touching the switch view.

Expected result: When the activity first starts, the claw with will be in a close (Claw Close) state and when a user switches the claw on, the claw should be in a Claw Open state.

Case 4: Joystick database:

Purpose: To store the values of the servos on where they are supposed to move

Precondition/Steps: The requirements for this table is 4 INT values for servo 1, servo 2, servo 3, and servo 4. The values are received from the left and right joysticks.

Expected result: When the activity first starts, the claw with will be in a close (Claw Close) state and when a user switches the claw on, the claw should be in a Claw Open state.