



main.cpp

```
1  #include <GL/glut.h>
2
3  static int shoulderAngle = 0, elbowAngle = 0;
4
5  void special(int key, int, int) {
6      switch (key) {
7          case GLUT_KEY_LEFT: (elbowAngle -= 10); break;
8          case GLUT_KEY_RIGHT: (elbowAngle += 10); break;
9          case GLUT_KEY_UP: (shoulderAngle += 10); break;
10         case GLUT_KEY_DOWN: (shoulderAngle -= 10); break;
11         default: return;
12     }
13     glutPostRedisplay();
14 }
15
16 void wireBox(GLdouble width, GLdouble height, GLdouble depth) {
17     glPushMatrix();
18     glScalef(width, height, depth);
19     glutWireCube(1.0);
20     glPopMatrix();
21 }
22
23 void display() {
24
25     glClear(GL_COLOR_BUFFER_BIT);
26     glMatrixMode(GL_MODELVIEW);
27     glPushMatrix();
28
29     glRotatef((GLfloat)shoulderAngle, 0.0, 1.0, 0.0);
30     glTranslatef(1.0, 0.0, 0.0);
31     wireBox(2.0, 0.4, 1.0);
32
33     glTranslatef(1.0, 0.0, 0.0);
34     glRotatef((GLfloat)elbowAngle, 0.0, 0.0, 1.0);
35     glTranslatef(1.0, 0.0, 0.0);
```

Robot Arm



C/C++

Windows (CR+LF)

WINDOWS-1252

Line 68, Col 1, Pos 1624

Insert

Read/Write



31°C Cloudy

