test.ino

```
#include
// Create a new servo object:
Servo myservo1;
Servo myservo2;Servo myservo3;
Servo myservo4;
Servo myservo5;
Servo myservo6;

// Define the servo pin:
#define servoPin1 9
#define servoPin2 11
#define servoPin3 10
#define servoPin4 6
#define servoPin5 5
#define servoPin6 3

// Create a variable to store the servo position:
int angle = 0;

void rot()
{
int i;
for(i=0;i<3;i++)
{
myservo1.write(45);
myservo2.write(135);
myservo3.write(45);
myservo4.write(135);
myservo5.write(45);
myservo6.write(135);
delay(1000);
myservo1.write(135);
myservo2.write(45);
myservo3.write(135);
myservo4.write(45);
myservo5.write(135);
myservo6.write(45);
delay(1000);
}
}
void ttt()
{
int i;
for(i=0;i<3;i++)
{
myservo1.write(45);
myservo2.write(45);
myservo3.write(45);
myservo4.write(45);
myservo5.write(45);
myservo6.write(45);
```

```
delay(1000);
myservo1.write(135);
myservo2.write(135);
myservo3.write(135);
myservo4.write(135);
myservo5.write(135);
myservo6.write(135);
delay(1000);
}

}

void xt()
{
int i;
for(i=0;i<3;i++)
{
myservo1.write(135);
myservo2.write(45);
myservo3.write(90);
myservo4.write(135);
myservo5.write(45);
myservo6.write(90);
delay(1000);
myservo1.write(45);
myservo2.write(135);
myservo3.write(90);
myservo4.write(45);
myservo5.write(135);
myservo6.write(90);
delay(1000);
}

}
void ytra()
{
int i;
for(i=0;i<3;i++)
{
myservo1.write(90);
myservo2.write(45);
myservo3.write(45);
myservo4.write(135);
myservo5.write(135);
myservo6.write(90);
delay(1000);
myservo1.write(90);
myservo2.write(90);
myservo3.write(135);
myservo4.write(45);
myservo5.write(45);
myservo6.write(90);
delay(1000);
}
}
```

```
void yt()
{
int i;
for(i=0;i<3;i++)
{
myservo1.write(135);
myservo2.write(90);
myservo3.write(45);
myservo4.write(135);
myservo5.write(90);
myservo6.write(45);
delay(1000);
myservo1.write(45);
myservo2.write(90);
myservo3.write(135);
myservo4.write(45);
myservo5.write(90);
myservo6.write(135);
delay(1000);
}

}


void xtra()
{
int i;
for(i=0;i<3;i++)
{
myservo1.write(45);
myservo2.write(135);
myservo3.write(135);
myservo4.write(90);
myservo5.write(90);
myservo6.write(45);
delay(1000);
myservo1.write(135);
myservo2.write(45);
myservo3.write(45);
myservo4.write(90);
myservo5.write(90);
myservo6.write(135);
delay(1000);
}
}
```

```
void setup() {
// Attach the Servo variable to a pin:
myservo1.attach(servoPin1);
myservo2.attach(servoPin2);
```

```
myservo3.attach(servoPin3);
myservo4.attach(servoPin4);
myservo5.attach(servoPin5);
myservo6.attach(servoPin6);


}


void loop() {
xtra();
xt();
ytra();
yt();
rot();
ttt();
delay(25000);

// Tell the servo to go to a particular angle:

}
```