// by \x6b\x69\x72\x61

#include <Servo.h>

Servo gripper;

Servo wrist;

Servo elbow;

Servo shoulder;

Servo base;

double base\_angle=90;

double shoulder\_angle=90;

double elbow\_angle=90;

double wrist\_angle=90;

void setup() {

Serial.begin(115200);

base.attach(8);

shoulder.attach(9);

elbow.attach(10);

wrist.attach(11);

gripper.attach(12);

base.write(base\_angle);

shoulder.write(shoulder\_angle);

elbow.write(elbow\_angle);

wrist.write(wrist\_angle);

}

String getValue(String data, char separator, int index)

{

int found = 0;

int strIndex[] = {0, -1};

int maxIndex = data.length()-1;

for(int i=0; i<=maxIndex && found<=index; i++){

if(data.charAt(i)==separator || i==maxIndex){

found++;

strIndex[0] = strIndex[1]+1;

strIndex[1] = (i == maxIndex) ? i+1 : i;

}

}

return found>index ? data.substring(strIndex[0], strIndex[1]) : "";

}

void loop() {

String computerText = Serial.readStringUntil('@');

computerText.trim();

if (computerText.length() == 0) {

return;

}

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String command = getValue(computerText, ' ',0);

if (command == "right" || command == "رايت" || command == "Right") {

base.write(base\_angle -= 20);

}

if (command == "left" || command == "Left" || command == "لفت") {

base.write(base\_angle += 20);

}

if (command == "top" || command == "توب" || command == "Top") {

shoulder.write(shoulder\_angle -= 20);

}

if (command == "bottom"|| command == "بوتوم" || command == "Bottom") {

shoulder.write(shoulder\_angle += 20);

}

Serial.println(command);

Serial.println("WORKING");

delay(1000);

}