#include<Servo.h>

#include<AFMotor.h>

// delay(milliseconds)

AF\_Stepper motorx(48,2); //X axis Port no 2

/\*class\_name object(parameter1,parameter2)

paramter1 = No of Steps

paramter2 = Port no in Shield \*/

AF\_Stepper motory(48,1);  //Y axis motor no 1

Servo servo1; // class\_name object;

int i,Speed = 50,steps = 50;

void setup() {

  Serial.begin(9600);

  motorx.setSpeed(Speed);

  motory.setSpeed(Speed);

  /\*class\_name.member\_func(parameter);

    parameter = speed value(RPM)\*/

  servo1.attach(10);

}

void loop() {

  motorx.step(steps,FORWARD,MICROSTEP);

  motory.step(steps,FORWARD,MICROSTEP);

  delay(100);

  motorx.step(steps,BACKWARD,MICROSTEP);

  motory.step(steps,BACKWARD,MICROSTEP);

  delay(100);

  /\*object.func(no\_of\_steps,DIRECTION,MODE);

    object=motorx and motory

    func= step() inside AF\_Stepper class

    DIRECTION = FORWARD & BACKWARD

    MODE = SINGLE, DOUBLE, MICROSTEP

  \*/

  servo1.write(0); //object.func(int); parameter(int)=angle < 200

  delay(1000); // 1000ms=1sec

  servo1.write(60);

  delay(1000);

  for(i=0;i<=180;i++)

  {

     servo1.write(i);// 1 degree rotate per millisecond

     delay(100);

  }

  /\*stop steppers

    motorx.release();

    motory.release();\*/

}