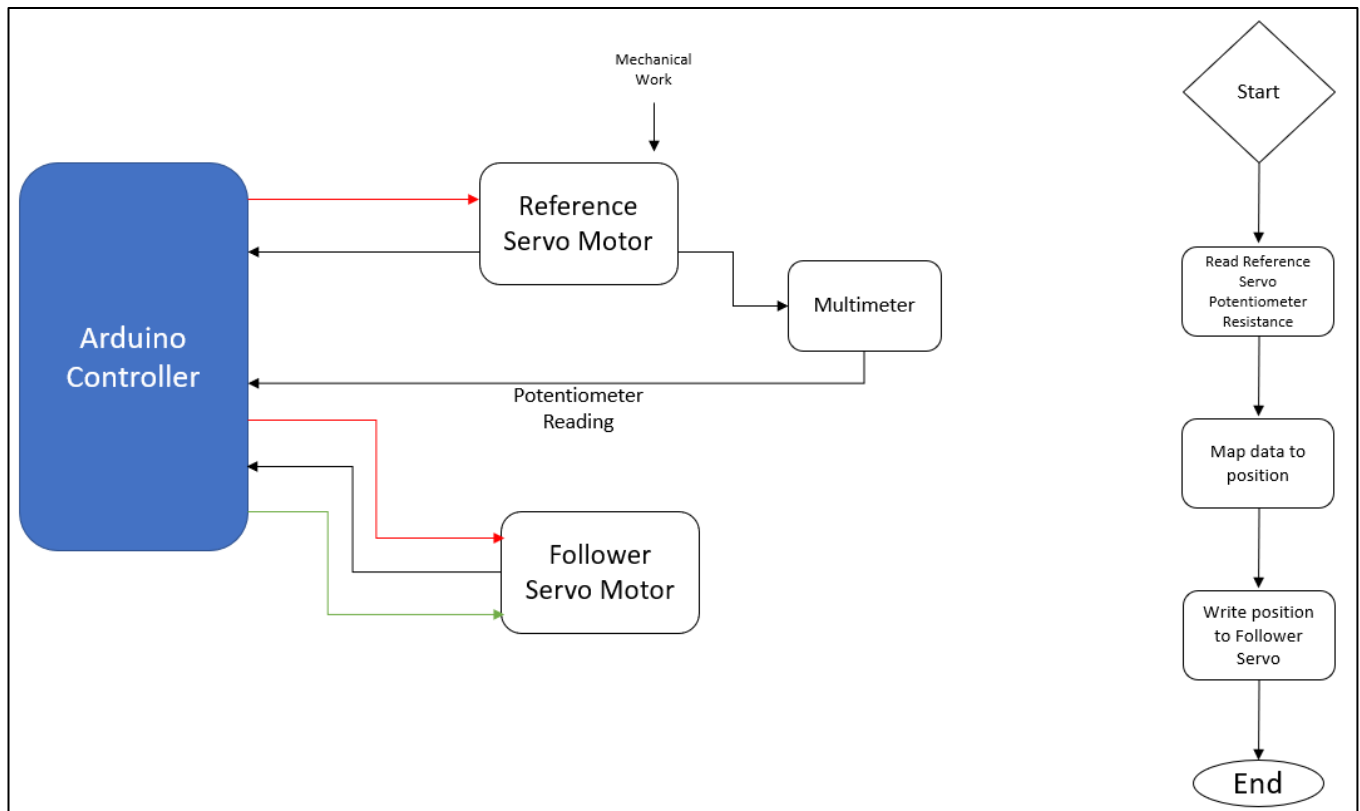


Algorithm:

1. The resistance of the reference servo motor is read.
2. The obtained data is mapped to position coordinates.
3. The position coordinates are written to the follower servo.

Note: Tinkercad does not allow servos to be moved mechanically. To simulate the effect of mechanically moving the servo motors using external force, a potentiometer was placed and connected to the servo to determine its position.



Code:

```
#include <Servo.h>

Servo reference;
Servo follow;

int pos_r = 0; // variable to store the servo position
int pos_f=0;

void setup() {
  reference.attach(5);
  follow.attach(3);
  pinMode(A5,INPUT);
  pinMode(A4,INPUT);
}

void loop() {

  pos_r=analogRead(A5); //reference position
  pos_r=map(pos_r,0,1023,0,180);

  delay(500);

  pos_f=analogRead(A4); // Follower Position
  pos_f=map(pos_f,0,1023,0,180);
  follow.write(pos_f);

}
```