CODING:

GLOVE(KIT 1):

```
// Pin Definitions
const int x1 = A0; // X-axis pin
const int x2 = A1; // Y-axis pin
const int x3= A2; // Z-axis pin
const int x4 = A3; // X-axis pin
const int x5 = A4; // Y-axis pin
// Threshold values for forward/reverse/left/right
void setup() {
  // Initialize relay pins as outputs
  pinMode(x1,INPUT);
  pinMode(x2,INPUT);
  pinMode(x3,INPUT);
  pinMode(x4,INPUT);
  pinMode(x5,INPUT);
  // Start the Serial Monitor
  Serial.begin(9600);
}
void loop() {
  // Read the accelerometer values
  int Value1 = analogRead(x1);
  int Value2 = analogRead(x2);
  int Value3 = analogRead(x3);
```

```
  int Value4 = analogRead(x4);
  int Value5 = analogRead(x5);
  // Print the accelerometer values to Serial Monitor
  Serial.print("X1: ");
  Serial.print( Value1);
  Serial.print("x2: ");
  Serial.print( Value2);
  Serial.print("x3: ");
  Serial.print( Value3);
  Serial.print("x4: ");
  Serial.print( Value4);
  Serial.print("x5: ");
  Serial.println( Value5);
if(Value1>=270&&Value1<290)
{
  Serial.print('A');
  delay(300);
}
else
{

}
if(Value2>=270&&Value2<290)
{
  Serial.print('B');
   delay(300);
}
```

```
if(Value3>=270&&Value3<290)
{
  Serial.print('C');
   delay(300);
}
if(Value4>=270&&Value4<290)
{
  Serial.print('D');
   delay(300);
}
if(Value5>=270&&Value5<290)
{
  Serial.print('E');
   delay(300);
}
delay(1000);
  // Check for forward or reverse based on X-axisf
 // Small delay to stabilize
}
```

ROBOT HAND(KIT 2):

```
#include <Servo.h>
// Declare servo objects
Servo servo1;
Servo servo2;
Servo servo3;
```

```
Servo servo4;
Servo servo5;
// Define individual pins for each servo
int servoPin1 = 3;
int servoPin2 = 5;
int servoPin3 = 6;
int servoPin4 = 9;
int servoPin5 = 10;
void setup() {
  // Attach each servo to its respective pin
  servo1.attach(servoPin1);
  servo2.attach(servoPin2);
  servo3.attach(servoPin3);
  servo4.attach(servoPin4);
  servo5.attach(servoPin5);
  Serial.begin(9600);
  servo1.write(0);
      servo2.write(0);
       servo3.write(0);
       servo4.write(0);
        servo5.write(0);
}
void loop() {
  if (Serial.available()) {
    char input = Serial.read();
    if (input == 'A') {
      // Move all servos to 0 degrees
```

```
    servo1.write(0);
    servo2.write(0);
    servo3.write(0);
    servo4.write(0);
    servo5.write(0);
    delay(2000);
    // Then move all servos to 90 degrees
    servo1.write(180);
    servo2.write(90);
    servo3.write(90);
    servo4.write(90);
    servo5.write(90);
    delay(2000);
  }
  if (input == 'B') {
      servo1.write(0);
  }
  if (input == 'C') {
    servo2.write(90);
  }
  if (input == 'D') {
    servo2.write(0);
  }
if (input == 'E') {
    servo3.write(90);
  }
  if (input == 'F') {
```

```
      servo3.write(0);
    }
    if (input == 'G') {
      servo4.write(90);
    }
     if (input == 'H') {
      servo4.write(0);
    }
    if (input == 'I') {
      servo5.write(90);
    }
     if (input == 'J') {
      servo5.write(0);
    }
  }
}
```