* ~~Moving correct joints with program~~
* ~~Nothing else will happen in the Arduino code after moving joints~~
* ~~No delays still left in~~
* ~~Right joints are enabled in code~~
* ~~Right code is uploaded~~
* ~~No physical limits it will hit~~
* ~~In position close to start pos~~
* ~~Movement speed set (default 3 seconds move\_speed command)~~
* ~~No tape on moving joints~~
* ~~Tape on joints not moving~~
* ~~Right fuses in~~
* ~~Turned off when uploaded then reset then turned on~~
* ~~Plugged in~~