#include <SoftwareSerial.h>

SoftwareSerial mySerial(0,1);

int func=0;

#define ACW 2 //CW is defined as pin #2//

#define ACCW 3//CCW is defined as pin #3//

#define BCW 4

#define BCCW 5

#define CCW 6

#define CCCW 7

#define DCW 8

#define DCCW 9

#define ECW 10

#define ECCW 11

void setup() { //Setup runs once//

Serial.begiAn(9600); //open the serial port

mySerial.begin(9600); // open the bluetooth serial port

pinMode(ACW, OUTPUT); //Set ACW as an output//

pinMode(ACCW, OUTPUT); //Set ACCW as an output//

pinMode(BCW, OUTPUT); // motor 2//

pinMode(BCCW, OUTPUT);

pinMode(CCW, OUTPUT); // motor 3//

pinMode(CCCW, OUTPUT);

pinMode(DCW, OUTPUT); // motor 4//

pinMode(DCCW, OUTPUT);

pinMode(ECW, OUTPUT); // motor 5//

pinMode(ECCW, OUTPUT);

}

void loop() { //Loop runs forever//

if(mySerial.available()){

Serial.println(mySerial.readString()); // send from serial to bluetooth

}

if(Serial.available()){

mySerial.println(Serial.readString());// send from bluetooth to serial

}

// send data only when you receive data:

if (Serial.available() > 0) {

// read the incoming byte:

func = Serial.read();

}

if(func == 1){//hand and leg flexion & extension//

// motor 1//

digitalWrite(ACW,HIGH); //Motor runs clockwise//

delay(5000); //for 5 second//

digitalWrite(ACW, LOW); //Motor stops//

digitalWrite(ACCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(ACCW, LOW); //Motor stops//

// motor 2//

digitalWrite(BCW,HIGH); //Motor runs clockwise//

delay(5000); //for 5 second//

digitalWrite(BCW, LOW); //Motor stops//

digitalWrite(BCCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(BCCW, LOW); //Motor stops//

// motor 3 //

digitalWrite(CCW,HIGH); //Motor runs clockwise//

delay(5000); //for 5 second//

digitalWrite(CCW, LOW); //Motor stops//

digitalWrite(CCCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(CCCW, LOW); //Motor stops//

// motor 4//

digitalWrite(ACW,HIGH); //Motor runs clockwise//

delay(5000); //for 5 second//

digitalWrite(ACW, LOW); //Motor stops//

digitalWrite(ACCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(ACCW, LOW); //Motor stops//

}

if(func==){//flexion & extension stop//

}

if(func==2){//palm and foot up and down//

//motor3//

digitalWrite(CCW,HIGH); //Motor runs clockwise//

delay(5000); //for 5 second//

digitalWrite(CCW, LOW); //Motor stops//

digitalWrite(CCCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(CCCW, LOW); //Motor stops//

// motor 4//

digitalWrite(DCW,HIGH); //Motor runs clockwise//

delay(5000); //for 5 second//

digitalWrite(DCW, LOW); //Motor stops//

digitalWrite(DCCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(DCCW, LOW); //Motor stops//

}

if(func==){//palm up and palm dowun stop//

}

if(func ==3){//palm,foot left,right//

// motor 3//

digitalWrite(CCW,HIGH); //Motor runs clockwise//

delay(5000); //for 5 second//

digitalWrite(CCW, LOW); //Motor stops//

// motor 4//

digitalWrite(DCW,HIGH); //Motor runs clockwise//

delay(5000); //for 5 second//

digitalWrite(DCW, LOW); //Motor stops//

// motor 5//

digitalWrite(ACW,HIGH); //Motor runs clockwise//

delay(2000); //for 5 second//

digitalWrite(ACW, LOW); //Motor stops//

digitalWrite(ACCW, HIGH);//Motor runs counter-clockwise//

delay(2000); //For 5 second//

digitalWrite(ACCW, LOW); //Motor stops//

}

if(func==){//palm left,right stop//

}

if(func==4){//adduction &abduction//

// motor 5//

digitalWrite(ACW,HIGH); //Motor runs clockwise//

delay(2000); //for 5 second//

digitalWrite(ACW, LOW); //Motor stops//

digitalWrite(ACCW, HIGH);//Motor runs counter-clockwise//

delay(2000); //For 5 second//

digitalWrite(ACCW, LOW); //Motor stops//

}

if(func==){//adduction & abduction//

}

if(func ==0){// over all stop//

//motor 1//

digitalWrite(ACW, LOW);

digitalWrite(ACCW, LOW);

digitalWrite(ACCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(ACCW, LOW);

//motor 2//

digitalWrite(BCW, LOW);

digitalWrite(BCCW, LOW);

digitalWrite(BCCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(BCCW, LOW);

//motor 3//

digitalWrite(CCW, LOW);

digitalWrite(CCCW, LOW);

digitalWrite(CCCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(CCCW, LOW);

//motor 4//

digitalWrite(DCW, LOW);

digitalWrite(DCCW, LOW);

digitalWrite(DCCW, HIGH);//Motor runs counter-clockwise//

delay(5000); //For 5 second//

digitalWrite(DCCW, LOW);

//motor 5//

digitalWrite(ECW, LOW);

digitalWrite(ECCW, LOW);

digitalWrite(ECCW, HIGH);//Motor runs counter-clockwise//

delay(2000); //For 5 second//

digitalWrite(ECCW, LOW);

}

}