```
from lx16a import *
LX16A.initialize("/dev/ttyUSB0")

servo1 = LX16A(1)
servo2 = LX16A(2)
servo3 = LX16A(3)
servo4 = LX16A(4)
servo5 = LX16A(5)
servo6 = LX16A(6)

servo1.moveTimeWaitWrite(132, 5000)
servo2.moveTimeWaitWrite(114, 5000)
servo3.moveTimeWaitWrite(120, 5000)
servo4.moveTimeWaitWrite(147, 5000)
servo5.moveTimeWaitWrite(140, 5000)
servo6.moveTimeWaitWrite(132, 5000)

# Sleep for one second
time.sleep(2)

# Starts rotation of the servo

LX16A.moveStartAll()
```

Health Test Routine:

```
from lx16a import *
LX16A.initialize("/dev/ttyUSB0")

servo1 = LX16A(1)
servo2 = LX16A(2)
servo3 = LX16A(3)
servo4 = LX16A(4)
servo5 = LX16A(5)
servo6 = LX16A(6)

print("The health check results for servo " , servo1.IDRead())
print("Max. legal input voltage=", servo1.vInLimitRead())
print("Current input voltage to servo=", servo1.vInRead())
print("Max. legal temperature of the servo=",servo1.tempMaxLimitRead())
print("Current temperature of the servo=", servo1.tempRead())

print("\n")
print("\n")

print("The health check results for servo " , servo2.IDRead())
print("Max. legal input voltage=", servo2.vInLimitRead())
print("Current input voltage to servo=", servo2.vInRead())
print("Max. legal temperature of the servo=",servo2.tempMaxLimitRead())
print("Current temperature of the servo=", servo2.tempRead())



print("\n")
print("\n")

print("The health check results for servo " , servo3.IDRead())
print("Max. legal input voltage=", servo3.vInLimitRead())
print("Current input voltage to servo=", servo3.vInRead())
```

```
print("Max. legal temperature of the servo=",servo3.tempMaxLimitRead())
print("Current temperature of the servo=", servo3.tempRead())

print("\n")
print("\n")

print("The health check results for servo " , servo4.IDRead())
print("Max. legal input voltage=", servo4.vInLimitRead())
print("Current input voltage to servo=", servo4.vInRead())
print("Max. legal temperature of the servo=",servo4.tempMaxLimitRead())
print("Current temperature of the servo=", servo4.tempRead())

print("\n")
print("\n")

print("The health check results for servo " , servo5.IDRead())
print("Max. legal input voltage=", servo5.vInLimitRead())
print("Current input voltage to servo=", servo5.vInRead())
print("Max. legal temperature of the servo=",servo5.tempMaxLimitRead())
print("Current temperature of the servo=", servo5.tempRead())

print("\n")
print("\n")

print("The health check results for servo " , servo6.IDRead())
print("Max. legal input voltage=", servo6.vInLimitRead())
print("Current input voltage to servo=", servo6.vInRead())
print("Max. legal temperature of the servo=",servo6.tempMaxLimitRead())
print("Current temperature of the servo=", servo6.tempRead())
```

Motor angles as a function of time:

```
from lx16a import *
From matplotlib.pyplot import plt
LX16A.initialize("/dev/ttyUSB0")

servo1 = LX16A(1)
servo2 = LX16A(2)
servo3 = LX16A(3)
servo4 = LX16A(4)
servo5 = LX16A(5)
servo6 = LX16A(6)

s1=[]
s2=[]
s3=[]
s4=[]
s5=[]
s6=[]
time=[]

s1.append(ANGLE)
time.append
```