Code FASH HACKS:

#include<SoftwareSerial.h>

SoftwareSerial bt(2,3); /\* (Rx,Tx) \*/

int FLEX\_PIN1 = A0;

int flexADC1 = 0;

int sensorMin1 = 745;

int sensorMax1 = 815;

int FLEX\_PIN2 = A1;

int flexADC2 = 0;

int sensorMin2 = 740;

int sensorMax2 = 840;

int FLEX\_PIN3 = A2;

int flexADC3 = 0;

int sensorMin3 = 715;

int sensorMax3 = 820;

int FLEX\_PIN4 = A3;

int flexADC4 = 0;

int sensorMin4 = 760;

int sensorMax4 = 870;

int FLEX\_PIN5 = A4;

int flexADC5 = 0;

int sensorMin5 = 740;

int sensorMax5 = 835;int xpin = A5;

int xadc = 0;

int ypin = A6;

int yadc = 0;

char letter = ' ';

void setup() {

// put your setup code here, to run once:

Serial.begin(1200);

bt.begin(9600);

float flexADC1 = analogRead(FLEX\_PIN1);

if(flexADC1<sensorMin1){sensorMin1=flexADC1;}

if(flexADC1>sensorMax1){sensorMax1=flexADC1;}

float flexADC2 = analogRead(FLEX\_PIN2);

if(flexADC2<sensorMin2){sensorMin2=flexADC2;}

if(flexADC2>sensorMax2){sensorMax2=flexADC2;}

float flexADC3 = analogRead(FLEX\_PIN3);

if(flexADC3<sensorMin3){sensorMin3=flexADC3;}

if(flexADC3>sensorMax3){sensorMax3=flexADC3;}

float flexADC4 = analogRead(FLEX\_PIN4);

if(flexADC4<sensorMin4){sensorMin4=flexADC4;}

if(flexADC4>sensorMax4){sensorMax4=flexADC4;}

float flexADC5 = analogRead(FLEX\_PIN5);

if(flexADC5<sensorMin5){sensorMin5=flexADC5;}

if(flexADC5>sensorMax5){sensorMax5=flexADC5;}

}

void loop() {

// put your main code here, to run repeatedly:

Serial.print("angle1:")

float flexADC1 = analogRead(FLEX\_PIN1);

flexADC1 = constrain(flexADC1,sensorMin1, sensorMax1);

float angle1= map(flexADC1, sensorMin1, sensorMax1, 0, 90);

Serial.print(angle1);

Serial.print("\t");

Serial.print("angle2:");

float flexADC2 = analogRead(FLEX\_PIN2);

flexADC2 = constrain(flexADC2,sensorMin2, sensorMax2);

float angle2= map(flexADC2, sensorMin2, sensorMax2, 0, 90);

Serial.print(angle2);

Serial.print("\t");

Serial.print("angle3:");

float flexADC3 = analogRead(FLEX\_PIN3);

flexADC3 = constrain(flexADC3,sensorMin3, sensorMax3);

float angle3= map(flexADC3, sensorMin3, sensorMax3, 0, 90);

Serial.print(angle3);

Serial.print("\t");

Serial.print("angle4:");

float flexADC4 = analogRead(FLEX\_PIN4);

flexADC4 = constrain(flexADC4,sensorMin4, sensorMax4);

float angle4= map(flexADC4, sensorMin4, sensorMax4, 0, 90);

Serial.print(angle4);

Serial.print("\t");

Serial.print("angle5:");

float flexADC5 = analogRead(FLEX\_PIN5);

flexADC5 = constrain(flexADC5,sensorMin5, sensorMax5);

float angle5= map(flexADC5, sensorMin5, sensorMax5, 0, 90);

Serial.print(angle5);

Serial.print("\t");

Serial.print("x:");

xadc = analogRead(xpin);

Serial.print(xadc);

Serial.print("\t");

Serial.print("y:");

yadc = analogRead(ypin);

Serial.println(yadc);

bool horizantol (((xadc>=309)&&(xadc<=390))&&((yadc>=270)&&(yadc<=320))) ;

bool vertical = (((xadc>=410)&&(xadc<=462))&&((yadc>=310)&&(yadc<=405)));

bool equaliburium =(((xadc>=317)&&(xadc<=385))&&((yadc>=315)&&(yadc<=390)));

if((angle1<=40)&&(angle2>=60)&&(angle3>=72)&&(angle4>=68)&&(angle5>=72))

{Serial.println(letter);

letter = 'A';}

if((angle1>=35)&&(angle2<=15)&&(angle3<=15)&&(angle4<=15)&&(angle5<=15))

{Serial.println('B');

letter = 'B';}

if((angle1<20)&&((angle2>=30)&&(angle2<80))&&((angle3>=30)&&(angle3<85))&&((

angle4>=30)&&(angle4<85))&&((angle5>=30)&&(angle5<85)))

{Serial.println('C');

letter = 'C';}

if(((angle1>=30)&&(angle1<=70))&&(angle2<=15)&&(angle3>=60)&&(angle4>=40)&&(

angle5>=40)&& vertical)

{Serial.println('D');

letter = 'D';}

if((angle1>=85)&&(angle2>=85)&&(angle3>=85)&&(angle4>=85)&&(angle5>=85))

{Serial.println('E');

letter = 'E';}

if((angle1>=30)&&(angle2>=40)&&(angle3<=15)&&(angle4<=15)&&(angle5<=15))

{Serial.println('F');

letter = 'F';}

if((angle1<=30)&&(angle2<=15)&&(angle3>=55)&&(angle4>=55)&&(angle5>=60)&&horizontal)

{Serial.println('G');

letter = 'G';}

if((angle1>=40)&&(angle2<=15)&&(angle3<=15)&&(angle4>=55)&&(angle5>=50)&&horizantol)

{Serial.println('H');

letter = 'H';}

if((angle1>=30)&&(angle2>=70)&&(angle3>=55)&&(angle4>=55)&&(angle5<=30)&&vertical)

{Serial.println('I');

letter='I';}

if((angle1>=30)&&(angle2>=70)&&(angle3>=55)&&(angle4>=55)&&(angle5<=30)&&!vertical)

{Serial.println('J');

letter='J';}

if((angle1<=30)&&(angle2<=15)&&(angle3<=15)&&(angle4>=55)&&(angle5>=55)&&vertical)

{Serial.println('K');

letter = 'K';}

if((angle1<=10)&&(angle2<=18)&&(angle3>=40)&&(angle4>=40)&&(angle5>=40)&&vertical)

{Serial.println('L');

letter = 'L';}

if(((angle1>=30)&&(angle1<=75))&&((angle2>=40)&&(angle2<80))&&((angle3>=40)&&(angle3<80))&&((angle4>=50)&&(angle4<=85))&&(angle5>=85))

{Serial.println('M');

letter = 'M';}

if(((angle1>=30)&&(angle1<=70))&&((angle2>=40)&&(angle2<80))&&((angle3>=40)&&(angle3<80))&&(angle4>85)&&(angle5>=85))

{Serial.println('N');

letter = 'N';}

if((angle1>=20)&&((angle2>=30)&&(angle2<80))&&((angle3>=30)&&(angle3<85))&&(

(angle4>=30)&&(angle4<85))&&((angle5>=30)&&(angle5<85))&&vertical)

{Serial.println('O');

letter ='O';}

if((angle1<=40)&&(angle2<=15)&&(angle3<=30)&&(angle4>=55)&&(angle5>=55)&&equilibrium)

{Serial.println('P');

letter = 'P';}

if((angle1<=15)&&(angle2<=15)&&(angle3>=50)&&(angle4>=50)&&(angle5>=60)&&equaliburium)

{Serial.println('Q');

letter = 'Q';}

if((angle1>=30)&&(angle2<=10)&&((angle3>=10)&&(angle3<=20))&&(angle4>=55)&&(

angle5>=55)&&vertical)

{Serial.println('R');

letter = 'R';}

if(((angle1>=60)&&(angle1<85))&&(angle2>=70)&&(angle3>=70)&&(angle4>=70)&&(angle5>=70))

{Serial.println('S');

letter = 'S';}

if(((angle1>=10)&&(angle1<=40))&&((angle2>=20)&&(angle2<=50))&&(angle3>=80)&&(angle4>=80)&&(angle5>=80))

{Serial.println('T');

letter = 'T';}

if((angle1>=30)&&(angle2<=10)&&(angle3<10)&&(angle4>=55)&&(angle5>=55)&&vertical)

{Serial.println('U');

letter = 'U';}

if((angle1>=30)&&(angle2<=10)&&(angle3<10)&&(angle4>=55)&&(angle5>=55)&&vertical)

{Serial.println('V');

letter = 'V';}

if((angle1>=40)&&(angle2<=10)&&(angle3<=15)&&(angle4<=15)&&(angle5>=55))

{Serial.println('W');

letter = 'W';}

if((angle1>=30)&&((angle2>=15)&&(angle2<=40))&&(angle3>=30)&&(angle4>=30)&&(

angle5>=30)&&vertical)

{Serial.println('X');

letter = 'X';}

if((angle1<=10)&&(angle2>=44)&&(angle3>=40)&&(angle4>=40)&&(angle5<=15))

{Serial.println('Y');

letter = 'Y';}

if(((angle1>=30)&&(angle1<=70))&&(angle2<=15)&&(angle3>=60)&&(angle4>=40)&&(

angle5>=40)&&!vertical)

{Serial.println('Z');

letter='Z';}

bt.write(letter);

delay(20);

}

ANOTHER CODE:

int a = 0;

int b = 0;

int c = 0;

int d = 0;

int e = 0;

void setup()

{

pinMode(A0, INPUT);

pinMode(A1, INPUT);

pinMode(A2, INPUT);

pinMode(A3, INPUT);

pinMode(A4, INPUT);

Serial.begin(9600);

}

void loop()

{

a = analogRead(A0); //thumb

c = analogRead(A1); //index

d = analogRead(A2); //middle

b = analogRead(A3); //ring

e = analogRead(A4); //little

Serial.println(a);

Serial.println(b);

Serial.println(c);

Serial.println(d);

Serial.println(e);

{

if (a < 900 && b > 900 && c > 900 && d > 900 && e > 900 && a > 800 ) {

Serial.println("a");

}

{

if (a > 900 && b < 900 && c < 900 && e < 900 ) {

Serial.println("b");

}

if (a > 900 && b < 900 && c > 900 && d > 800 && e > 900 ) {

Serial.println("d");

}

}

if (a > 900 && b > 900 && c > 900 && d > 900 && e > 900 ) {

Serial.println("e");

}

if (a > 900 && b > 900 && c < 890 && e < 890 ) {

Serial.println("f");

}

if (a < 900 && b < 900 && c > 890 && d > 890 && e > 890 && a > 800 ) {

Serial.println("g");

}

if (a < 900 && b < 900 && c < 900 && d > 870 && e > 900 ) {

Serial.println("h");

}

if (a > 900 && b > 900 && c > 900 && d > 900 && e < 900 ) {

Serial.println("i");

}

if (a < 900 && b > 900 && c > 900 && d > 900 && e < 900 && a > 800 ) {

Serial.println("j");

}

if (a > 900 && b < 900 && c < 900 && d > 900 && e > 900 ) {

Serial.println("k");

}

if (a < 800 && b < 900 && c > 900 && d > 900 && e > 900 ) {

Serial.println("l");

}

if (a < 800 && b > 900 && c > 900 && d > 900 && e < 900 ) {

Serial.println("m");

}

if (a < 820 && b > 900 && c > 900 && d < 900 && e < 900 ) {

Serial.println("n");

}

if (a > 820 && b < 900 && c < 900 && d < 900 && e > 900 ) {

Serial.println("o");

}

if (a < 880 && b < 910 && c > 900 && d > 900 && e < 890 ) {

Serial.println("p");

}

if (a < 850 && b < 900 && c > 900 && d < 920 && e < 890 ) {

Serial.println("q");

}

if (a < 790 && b < 900 && c < 900 && d > 920 && e > 890 ) {

Serial.println("r");

}

if (a < 960 && b > 900 && c > 900 && d > 920 && e > 890 && a > 940 ) {

Serial.println("s");

}

if (a < 800 && b > 900 && d < 920 && e < 890 ) {

Serial.println("t");

}

if (a > 900 && b < 900 && d > 900 && e < 900 ) {

Serial.println("u");

}

if (a > 900 && b < 900 && d < 900 && e < 900 && c > 900 ) {

Serial.println("v");

}

if (a < 900 && b < 900 && d < 900 && e < 900 && c > 900 ) {

Serial.println("w");

}

if (a > 900 && b > 900 && d < 900 && e < 900 && c > 900 ) {

Serial.println("x");

}

if (a > 800 && b > 900 && d < 900 && e > 900 && c > 900 ) {

Serial.println("y");

}

if (a > 900 && b > 900 && d < 900 && e < 900 && c > 900 ) {

Serial.println("z");

}

delay(2500);

}}