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#include <Servo.h>

Servo servothumb;    // Define thumb servo
Servo servoindex;    // Define index servo
Servo servomajeure;
Servo servoringfinger;
Servo servopinky;
Servo servowrist;
Servo servobiceps;
Servo servoshoulder;
Servo servoomoplat;

void setup() {
  servothumb.attach(2); // Set thumb servo to digital pin 2
  servoindex.attach(3); // Set index servo to digital pin 3
  servomajeure.attach(4);
  servoringfinger.attach(5);
  servopinky.attach(6);
  servowrist.attach(7);
  servobiceps.attach(8);
  servoshoulder.attach(9);
  servoomoplat.attach(10);
}

void loop() {        // Loop through motion tests
  allopen();          // Example: allopen
  delay(4000);         // Wait 4000 milliseconds (4 seconds)
  handclose();
  delay(4000);
  allopen();
  delay(2000);
  shoulderalone();
  delay(1000);
}

// Motion routines for handopen, handclose, victory...
void allopen() {
  servothumb.write(0);
  servoindex.write(0);
  servomajeure.write(0);
  servoringfinger.write(0);
  servopinky.write(0);
  servowrist.write(0);
  servobiceps.write(0); //Never more then (90 degree)
  servoshoulder.write(110); //Never more then (130 degree)
  servoomoplat.write(0);
}

```

```
void handclose() {
  servothumb.write(180);
  servindex.write(180);
  servomajeure.write(180);
  servoringfinger.write(180);
  servopinky.write(180);
  servowrist.write(180);
  servobiceps.write(85); //Never more then (90 degree)
  servoshoulder.write(90); //Never more then (130 degree)
  servoomoplat.write(180);
}

void shoulderalone() {
  servothumb.write(0);
  servindex.write(0);
  servomajeure.write(0);
  servoringfinger.write(0);
  servopinky.write(0);
  servowrist.write(90);
  servobiceps.write(85); //Never more then (90 degree)
  servoshoulder.write(130); //Never more then (130 degree)
  servoomoplat.write(0);
}
```