

```

#include <Servo.h>

Servo servothumb;    // Define left servo
Servo servindex;     // Define right servo
Servo servomajeure;
Servo servoringfinger;

void setup() {
  servothumb.attach(2); // Set left servo to digital pin 10
  servindex.attach(3);  // Set right servo to digital pin 9
  servomajeure.attach(4);
  servoringfinger.attach(5);
}

void loop() {        // Loop through motion tests
  handopen();         // Example: move forward
  delay(3000);         // Wait 2000 milliseconds (2 seconds)
  handclose();
  delay(2000);
  handopen() ;
  delay(1000);
  victory();
  delay(2000);
  handopen() ;
  delay(2000);
  pinchmode();
  delay(4000);
  openpinch();
  delay(2000);
  handopen() ;
  delay(2000);
  grab();
  delay(2000);
  handopen() ;
  delay(1000);
  thumbclose() ;
  delay(1000);
  ringfingerclose() ;
  delay(1000);
}

// Motion routines handopen, handclose, victory, grab...
void handopen() {
  servothumb.write(0);
  servindex.write(180);
  servomajeure.write(180);
  servoringfinger.write(180);
}

void handclose() {
  servindex.write(0);
  servomajeure.write(0);
}

```

```
servoringfinger.write(0);  
servothumb.write(180);  
}
```

```
void victory() {  
servothumb.write(180);  
servoindex.write(180);  
servomajeure.write(180);  
servoringfinger.write(0);  
}
```

```
void pinchmode() {  
servothumb.write(110);  
servoindex.write(80);  
  
}
```

```
void openpinch() {  
servothumb.write(0);  
servoindex.write(180);  
servomajeure.write(0);  
servoringfinger.write(0);  
  
}
```

```
void grab() {  
servothumb.write(110);  
servoindex.write(80);  
servomajeure.write(80);  
servoringfinger.write(20);  
  
}
```

```
void thumbclose() {  
servothumb.write(180);  
  
}
```

```
void ringfingerclose() {  
servoringfinger.write(0);  
  
}
```