CODES ARDUINO

/\* Sweep

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 This example code is in the public domain.

 modified 8 Nov 2013

 by Scott Fitzgerald

 http://www.arduino.cc/en/Tutorial/Sweep

\*/

#include <Servo.h>

Servo mx;  // create servo object to control a servo mx

Servo my;  // create servo object to control a servo my

Servo mz;  // create servo object to control a servo mz

// twelve servo objects can be created on most boards

int pos = 180;    // variable to store the servo position

int i = 0;      // variable to store the servox position

int j = 0;      // variable to store the servoy position

int k = 0;      // variable to store the servoz position

int l = 170;

int m = 0;

int n = 170;

void setup() {

  mx.attach(9);  // attaches the servo on pin 9 to the servo object

  my.attach(10); // attaches the servo on pin 9 to the servo object

  mz.attach(11); // attaches the servo on pin 9 to the servo object

  //pinMode(13,OUTPUT);

}

/\* Controler le volume UP  \*/

void loop() {

 digitalWrite(13,LOW);

  volume\_up();

}

void volume\_up() {

digitalWrite(13,HIGH);

  while(i == 0) {

    x\_mouv(140);

    i++;

    }

    while(j == 0) {

    y\_mouv(45);

    j++;

    }

    while(k == 0) {

    z\_mouv(160);

    k++;

    }

     while(l == 170) {

      x\_init(100);

      l -=l;

    }

    while(m == 0) {

      y\_init(60);

      m +=1;

    }

    while(n == 170) {

      z\_init(100);

      n -=l;

    }

  }

void x\_mouv(int dist) { // va vers la droit

    for (pos = 0; pos <= dist; pos +=1 ) { // goes from 0 degrees to dist degrees

    // in steps of 1 degree

    mx.write(pos);              // tell servo to go to position in variable 'pos'

    delay(100);                       // waits 15ms for the servo to reach the position

  }

}

void y\_mouv(int dist) { // va vers la droit

    for (pos = 170; pos >= dist; pos -=1 ) { // goes from 0 degrees to 180 degrees

    // in steps of 1 degree

    my.write(pos);              // tell servo to go to position in variable 'pos'

    delay(100);                       // waits 15ms for the servo to reach the position

  }

}

void z\_mouv(int dist) { // va vers la droit

    for (pos = 0; pos <= dist; pos +=1 ) { // goes from 0 degrees to dist degrees

    // in steps of 1 degree

    mz.write(pos);              // tell servo to go to position in variable 'pos'

    delay(20);                       // waits 15ms for the servo to reach the position

  }

/\* initialisation des axes \*/

}

void x\_init(int dist) { // va vers la droit

    for (pos = dist; pos <= 170; pos -= 1) { // goes from 0 degrees to 180 degrees

    // in steps of 1 degree

    mx.write(pos);              // tell servo to go to position in variable 'pos'

    delay(100);                       // waits 15ms for the servo to reach the position

  }

}

void y\_init(int dist) { // va vers la droit

    for (pos = dist; pos <= 170; pos -= 1) { // goes from 0 degrees to 180 degrees

    // in steps of 1 degree

    my.write(pos);              // tell servo to go to position in variable 'pos'

    delay(50);                       // waits 15ms for the servo to reach the position

  }

}

void z\_init(int dist) { // va vers la droit

    for (pos = dist; pos <= 170; pos -= 1) { // goes from 0 degrees to 180 degrees

    // in steps of 1 degree

    mz.write(pos);              // tell servo to go to position in variable 'pos'

    delay(50);                       // waits 15ms for the servo to reach the position

  }

}