Code pour la rotation du bol

```
#include <Servo.h>;

Servo myservo1;
Servo myservo2;
double long dumptimer;
double long lasttime;
bool isdumping = false;

int pos = 0;    // variable to store the servo position
bool isForward = false;

void setup() {
  myservo1.attach(5);  // attaches the servo on pin 9 to the servo object
  myservo2.attach(6);
  dumptimer=0;
  lasttime = millis();
}

void loop() {
  if (!isdumping)
{
  dumptimer += millis()-lasttime;
}
lasttime=millis();
if (dumptimer == 20000)
{
  dumptimer = 0;
  isdumping = true;
}

  if(pos < 180 && isForward){
    pos++;
    myservo1.write(pos);
    myservo2.write(180-pos);
  }
  if(pos > 0 && !isForward){
    pos--;
    myservo1.write(pos);
    myservo2.write(180-pos);
  }
  if(pos == 180 || pos == 0){
    isForward = !isForward;
  }
 delay(20);
}
```

Code pour le mouvement du bras

```
#include <Servo.h>
Servo myservo;
Servo myservo2;
Servo myservo3;
Servo myservo4;
void mix();
void lift();
void dumping();
int pos =0;
int i;
bool isForward = false;
void setup() {
  // put your setup code here, to run once:

myservo.attach(10);
myservo2.attach(11);
myservo3.attach(12);


}
void loop()
{
  for(i=0; i<= 3;i++)
   {
    mix();
   }
   lift();
   temp();
}
void mix()
{
myservo2.write(10);
myservo.write(0);
delay(2000);
myservo.write(180);
delay(2000);
}

void lift()
{
  myservo2.write(10);
  delay(2000);
  myservo2.write(90);
  delay(4000);
}
```

```
void temp()
{
  myservo3.write(0);
  delay(1000);
  myservo3.write(50);
  delay(1000);
  myservo3.write(180);
  delay(1000);
  myservo3.write(0);
}
```