```
#include <AccelStepper.h>

#define HALFSTEP 8

#define motorPin1 3
#define motorPin2 4
#define motorPin3 5
#define motorPin4 6

AccelStepper stepper1(HALFSTEP, motorPin1, motorPin3, motorPin2, motorPin4);

int rotation;

void setup() {

Serial.begin(9600);
stepper1.setMaxSpeed(5000.0);
stepper1.setAcceleration(500.0);

}

void loop() {

while (Serial.available() == 0) {}
```

```
rotation = Serial.parseInt();
rotation = rotation * 4076;
Serial.println(rotation);
if (rotation > 0) {
  while (stepper1.currentPosition() < rotation) {
  stepper1.moveTo(rotation);
  stepper1.run();
  Serial.println(stepper1.currentPosition());
  }
} else if (rotation < 0) {
  while (stepper1.currentPosition() > rotation) {
  stepper1.moveTo(rotation);
  stepper1.run();
  Serial.println(stepper1.currentPosition());
  }



}
stepper1.setCurrentPosition(0);
}
```