

```
Servo_SetAngle(int num, int angle)
  if num equals GrabberServo
    if angle equals 0
      set calcAngle equal to GrabberMax // open
    else
      set calcAngle equal to GrabberMin // closed
      call Servo12_SetPulseWidth(GrabberServo, 600+10*calcAngle)

  if num equals SpecialServo
    if angle <= 0x40
      set calcAngle equal to 170// forwards
    else
      set calcAngle equal to 0// backwards
      call Servo12_SetPulseWidth(SpecialServo, 600+10*calcAngle) ;
```