1. Create a System Restore Point on your computer

2. Install Arduino: https://www.arduino.cc/en/software/
   Install Updates & Allow Changes

3. Identify your Arduino "libraries" directory:
   a. File -> Preferences -> Sketchbook Location *e.g., c:\Users\Elijah\Documents\Arduino*

4. Remove the bluetooth module from your Robot Arm (if you installed it)

5. Plug-in Robot Arm to your computer **!!! IMPORTANT !!!**
   a. **Turn off battery power first**
   b. Plug in cord to Robot Arm first
   c. Lastly plug in USB end of cord to computer

6. Install "Default Program" library
   a. https://wiki.hiwonder.com/projects/miniArm/en/latest/docs/3.default_program_download.html
   b. Click on "Default Program" to download it, then extract/unzip it
   c. Navigate down two subdirs until you reach the MiniArm subdir
   d. Copy the MiniArm subdir to your Arduino libraries dir

7. Execute "Default Program"
   a. Arduino IDE -> File -> Open -> \libraries\MiniArm\miniArm.ino
   b. Select your Arduino Uno board (top left dropdown)
   c. Compile the program (top left check mark)
   d. Upload the program to your robot arm's Arduino board (top left arrow)
   e. Open the Serial Monitor (top right circle with dots)
   f. Keep your cord plugged in and power on your robot arm
   g. Hold K1 & K2 buttons until robot arm in neutral mode w/ green light

8. Install "Read Action" library
   a. https://wiki.hiwonder.com/projects/miniArm/en/latest/docs/6.motion_control_basic_course.html
   b. Click on "Read Action Data Program" to download read_mini.zip
   c. Extract/unzip it, navigate down one subdir and copy \read_mini to libraries dir

9. Execute "Read Action"
   a. \libraries\read_mini\read_mini.io
   b. Compile, Upload, Serial Monitor
   c. Cord plugged in, robot power on: Adjust servo knobs and observe joint angles

10. Upload "Default Program"
    1. Turn off battery power 2. Unplug USB from computer 3. Unplug cord from Robot