#define m1 3

#define m2 5

#define m3 9

#define m4 10

int arrow =0;

void setup() {

pinMode(m1,OUTPUT);

pinMode(m2,OUTPUT);

pinMode(m3,OUTPUT);

pinMode(m4,OUTPUT);

pinMode(12,INPUT);

pinMode(13,INPUT);

}

void loop() {

// pembacaan sensor pada pin 12 dan 13

int lsensor=digitalRead(12);

int rsensor=digitalRead(13);

//logika robot menggunakan prinsip AND

if((lsensor == LOW)&&(rsensor== HIGH))

{

// maju dengan kecepatan 100

motorOut(100,100,2);

}

if((lsensor== HIGH)&&(rsensor== LOW))

{

//belok kiri

motorOut(0,100,2);

}

if((lsensor==HIGH)&&(rsensor== HIGH))

{

motorOut(0,100,2);

//belok kiri

}

if((lsensor== LOW)&&(rsensor==LOW))

{

//belok kanan

motorOut(100,0,2);

}

}

//Fungsi untuk menggerakkan motor

void motorOut(unsigned char lpwm, unsigned char rpwm, int arrow){

//arrow =1 mundur, 2 maju,

if(arrow==1){

digitalWrite(m3,HIGH);

digitalWrite(m1,LOW);

analogWrite(m4,255-lpwm);

analogWrite(m2,rpwm);

}

else if (arrow==2)

{

digitalWrite(m3,LOW);

digitalWrite(m1,HIGH);

analogWrite(m4,lpwm);

analogWrite(m2,255-rpwm);

}

}

