

```
#include<Servo.h>

const int pingPin = 7;

int servoPin = 8;


Servo servo1;


void setup() {
  // initialize serial communication:
  Serial.begin(9600);
  servo1.attach(servoPin);
  pinMode(2,INPUT);
  pinMode(4,OUTPUT);
  pinMode(11,OUTPUT);
  pinMode(12,OUTPUT);
  pinMode(13,OUTPUT);
  pinMode(A0,INPUT);
  digitalWrite(2,LOW);
  digitalWrite(11,HIGH);

}


void loop() {

  long duration, inches, cm;


  pinMode(pingPin, OUTPUT);
  digitalWrite(pingPin, LOW);
  delayMicroseconds(2);
  digitalWrite(pingPin, HIGH);
```

```
delayMicroseconds(5);
digitalWrite(pingPin, LOW);

// The same pin is used to read the signal from the PING))) a HIGH pulse
// whose duration is the time (in microseconds) from the sending of the ping
// to the reception of its echo off of an object.
pinMode(pingPin, INPUT);
duration = pulseIn(pingPin, HIGH);

// convert the time into a distance
inches = microsecondsToInches(duration);
cm = microsecondsToCentimeters(duration);

//Serial.print(inches);
//Serial.print("in, ");
//Serial.print(cm);
//Serial.print("cm");
//Serial.println();
//delay(100);

servo1.write(0);

if(cm < 40)
{
    servo1.write(90);
    delay(2000);
}
else
{
```

```
servo1.write(0);  
}  
  
// PIR with LED starts  
int pir = digitalRead(2);  
  
if(pir == HIGH)  
{  
    digitalWrite(4,HIGH);  
    delay(1000);  
}  
else if(pir == LOW)  
{  
    digitalWrite(4,LOW);  
}  
  
//temp with fan  
float value=analogRead(A0);  
float temperature=value*0.48;  
  
Serial.println("temperature");  
Serial.println(temperature);  
  
if(temperature > 20)  
{  
    digitalWrite(12,HIGH);  
    digitalWrite(13,LOW);  
}  
else
```

```
{  
    digitalWrite(12,LOW);  
    digitalWrite(13,LOW);  
}  
}
```

```
long microsecondsToInches(long microseconds) {  
    return microseconds / 74 / 2;  
}
```

```
long microsecondsToCentimeters(long microseconds) {  
    return microseconds / 29 / 2;  
}
```