**HOME AUTOMATION SYSTEM**



**CODE:**

#include<Servo.h>

const int pingPin = 7;

int servoPin = 8;

int const gas\_sensor = A1;

int limit = 400;

Servo servo1;

void setup() {

// initialize serial communication:

Serial.begin(9600);

servo1.attach(servoPin);

pinMode(A1,INPUT); //gas sensor

pinMode(2,INPUT);//pir sensor

pinMode(4,OUTPUT); //resistor input

pinMode(11,OUTPUT); //h drive motor enable

pinMode(12,OUTPUT); //h drive input2

pinMode(13,OUTPUT); //h drive input1

pinMode(9,OUTPUT);// piezo input

pinMode(A0,INPUT);//temperature sesnor

digitalWrite(2,LOW); //make pir low

digitalWrite(11,HIGH); //enabling h motor drive

}

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);

// Automatic door using ultrasonic sensor

servo1.write(0);

Serial.print("|| Dist value = ");

Serial.println(cm);

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);

}

// Gas Sensor

int val = analogRead(gas\_sensor); //read sensor value

Serial.print("|| Gas Sensor Value = ");

Serial.println(val);

if (val > limit)

{

tone(9, 650);

}

delay(300);

noTone(9);

//temp with fan

float value=analogRead(A0);

float temperature=value\*0.48;

Serial.print("|| Temperature Value = ");

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;

}