CODE

```
        int trigPin = 9;      // trig pin of HC-SR04
int echoPin = 10;     // Echo pin of HC-SR04
int revleft4 = 4;       //REVerse motion of Left motor
int fwdleft5 = 5;       //ForWarD motion of Left motor
int revright6 = 6;      //REVerse motion of Right motor
int fwdright7 = 7;      //ForWarD motion of Right motor
long duration, distance;
void setup() {


  delay(random(500,2000));   // delay for random time
  Serial.begin(9600);
  pinMode(revleft4, OUTPUT);      // set Motor pins as output
  pinMode(fwdleft5, OUTPUT);
  pinMode(revright6, OUTPUT);
  pinMode(fwdright7, OUTPUT);


  pinMode(trigPin, OUTPUT);         // set trig pin as output
  pinMode(echoPin, INPUT);          //set echo pin as input to capture reflected wave
s
}
void loop() {
  digitalWrite(trigPin, LOW);
  delayMicroseconds(2);
  digitalWrite(trigPin, HIGH);     // send waves for 10 us
  delayMicroseconds(10);
```

```
  duration = pulseIn(echoPin, HIGH); // receive reflected waves
  distance = duration / 58.2;   // convert to distance
  delay(10);
    // If you dont get proper movements of your robot then alter the pin numbers
  if (distance > 19)
  {
    digitalWrite(fwdright7, HIGH);                    // move forward
    digitalWrite(revright6, LOW);
    digitalWrite(fwdleft5, HIGH);
    digitalWrite(revleft4, LOW)
;
  }
  if (distance < 18)
  {
    digitalWrite(fwdright7, LOW);  //Stop
    digitalWrite(revright6, LOW);
    digitalWrite(fwdleft5, LOW);
    digitalWrite(revleft4, LOW);
    delay(500);
    digitalWrite(fwdright7, LOW);      //movebackword
    digitalWrite(revright6, HIGH);
    digitalWrite(fwdleft5, LOW);
    digitalWrite(revleft4, HIGH);
    delay(500);
    digitalWrite(fwdright7, LOW);  //Stop
    digitalWrite(revright6, LOW);
    digitalWrite(fwdleft5, LOW);
```

```
    digitalWrite(revleft4, LOW);
    delay(100);
    digitalWrite(fwdright7, HIGH);
    digitalWrite(revright6, LOW);
    digitalWrite(revleft4, LOW);
    digitalWrite(fwdleft5, LOW);
    delay(500);
  }
}
```