#include<Servo.h>

#include <IRremote.hpp>

int mVal;

float sAngle;

int rcvPin=3;

IRrecv irrecv(rcvPin);

decode\_results results;

int reading = 0;

Servo servo\_11;

void setup()

{

Serial.begin(9600);

irrecv.enableIRIn();

pinMode(5, OUTPUT);

pinMode(6, OUTPUT);

pinMode(7, OUTPUT);

pinMode(8, OUTPUT);

pinMode(A0, INPUT);

pinMode(A1, INPUT);

pinMode(10,OUTPUT);

pinMode(12,INPUT);

servo\_11.attach(11);

}

void loop()

{

if(IrReceiver.decode()) {

auto value= IrReceiver.decodedIRData.decodedRawData;

{

switch(value)

{

case 4010852096:

Serial.println("1");

mVal = analogRead(A2);

Serial.println(mVal);

sAngle = (mVal \* (90./539.));

servo\_11.write(sAngle);

break;

case 3994140416:

Serial.println("2");

reading = analogRead(A1);

analogWrite(10,(reading\*0.75 - 15.09));

servo\_11.write((reading\*0.53-10.65));

break;

case 3977428736:

Serial.println("3");

analogWrite(10,(reading\*0.18));

servo\_11.write((reading\*0.53-10.65));

default: Serial.println(value);

}

IrReceiver.resume();

}

}

}