```cpp
  int trigPin = 3;      //Right Ultrasonic Sensor
  int echoPin = 2;
  long duration, distance ;
  #define R_sensor 8

  int trigPin2 = 4;     //Left Ultrasonic Sensor
  int echoPin2 = 5;
  long duration2, distance2 ;
  #define L_sensor 9

  //################## CLASS begin ################

  class A  //..........Code for Right Ultrasonic Sensor...............
  {
    public:

      void f() {
       digitalWrite(trigPin, LOW);
      delayMicroseconds(5);
      digitalWrite(trigPin, HIGH);
      delayMicroseconds(10);
      digitalWrite(trigPin, LOW);

      pinMode(echoPin, INPUT);
      duration = pulseIn(echoPin, HIGH);

      // convert the time into a distance
      distance = (duration/2) / 29.1;

      Serial.print("Distance Right: ");
      Serial.print(distance);
      Serial.print("cm           ");

      }   //end of void f
  };
  //...............................end of class A...................................

  class B   //..........Code for Left Ultrasonic Sensor...............
  {
    public:

      void f() {
          digitalWrite(trigPin2, LOW);
      delayMicroseconds(5);
      digitalWrite(trigPin2, HIGH);
      delayMicroseconds(10);
      digitalWrite(trigPin2, LOW);

      pinMode(echoPin2, INPUT);
      duration2 = pulseIn(echoPin2, HIGH);

      // convert the time into a distance
      distance2 = (duration2/2) / 29.1;

      Serial.print("Distance Left: ");
      Serial.print(distance2);
      Serial.println("cm          ");
      }    //end of void f

  };
  //.................................end of class B...................................

  // Method for call class
  A *a;
  B *b;
```

```
void setup()      // main function
{
    a=new A();
    b=new B();

    Serial.begin (9600);

    pinMode(trigPin, OUTPUT);
    pinMode(echoPin, INPUT);
    pinMode(R_sensor, OUTPUT);


    pinMode(trigPin2, OUTPUT);
    pinMode(echoPin2, INPUT);
    pinMode(L_sensor, OUTPUT);

    pinMode(22, OUTPUT); //Center LED
    pinMode(42, OUTPUT); //Right LED
    pinMode(44, OUTPUT); //Left LED
}

void loop()     //Continues loop
{


    b->f();
     a->f();
      digitalWrite(22,HIGH);  // ON Green LED

//..................Right Side LED+Sensor...........
    if(distance<=25 && distance>0)
    {Right(200);
     digitalWrite(42,HIGH);
    }
    else if(distance<=50 && distance>25)
    {Right(500);
     digitalWrite(42,HIGH);
    }
    else if(distance<=100 && distance>50)
    {Right(1000);
     digitalWrite(42,HIGH);
    }
    else{digitalWrite(8,LOW);
         digitalWrite(42,LOW);

    }
//..................Left Side LED+Sensor...........
    if(distance2<=25 && distance2>0)
    {Left(200);
     digitalWrite(44,HIGH);
    }
    else if(distance2<=50 && distance2>25)
    {Left(500);
      digitalWrite(44,HIGH);
     }
    else if(distance2<=100 && distance2>50)
    {Left(1000);
      digitalWrite(44,HIGH);
     }

    else{digitalWrite(9,LOW);
          digitalWrite(44,LOW);


      }
}  //..................................End of loop...................................
```

```
void Right (int interval){
   static long prevMill = 0;
   if (((long)millis() - prevMill) >= interval){
    prevMill = millis();
    digitalWrite(R_sensor, !digitalRead(R_sensor));
  }
 }

 void Left (int interval){
   static long prevMill = 0;
   if ((millis() - prevMill) >= interval){
    prevMill = millis();
    digitalWrite(L_sensor, !digitalRead(L_sensor));
  }
 }
//...................................END of Programme.................................
```