Using two push button and slider swtith taking hexadecimal value(robo-l code for slate)..

const int endirPin = 2;

const int startirPin = 3;

const int irPins[] = {4, 5, 6, 7, 8, 9, 10, 11};  // Example IR sensor pins

const int bufferSize = 100;

byte buffer[bufferSize];

const int index = 0;

byte irData;

const int bufferToHex;

#define HEX

void setup() {

  pinMode(endirPin, INPUT);

  pinMode(startirPin, INPUT);

  for (int i = 0; i < 8; i++) {

    pinMode(irPins[i], INPUT);

  }

**Serial**.begin(9600);

}

void loop() {

  // Check if both endir and startir are LOW to read binary data

  if (digitalRead(endirPin) == LOW && digitalRead(startirPin) == HIGH) {

    for(int index=0; index<bufferSize  ;index++)

    {

    // Read and store binary values of the IR sensors in the buffer

    for (int i = 0; i < 8; i++) {

      irData=((digitalRead(irPins[7]\*128 ))||(digitalRead(irPins[6]\*64)) ||(digitalRead(irPins[5]\*32)) ||(digitalRead(irPins[4]\*16))||(digitalRead(irPins[3]\*8)) || (digitalRead(irPins[2]\*4)) ||(digitalRead(irPins[1]\*2)) ||(digitalRead(irPins[0]\*1 )));

      //irData = digitalRead(irPins[i]);

      buffer[index] = irData;

**Serial**.print(irData) ;

     // index++;

    // int j=((i,HEX ) );

      //Serial.println((j));  // Print hexecimal value

    }

    }

    // Check if the buffer is full

    //if (index >= bufferSize) {

      // Process the buffer

      //processBuffer(buffer);

      //index = 0; // Reset the buffer index

   // }

 // }