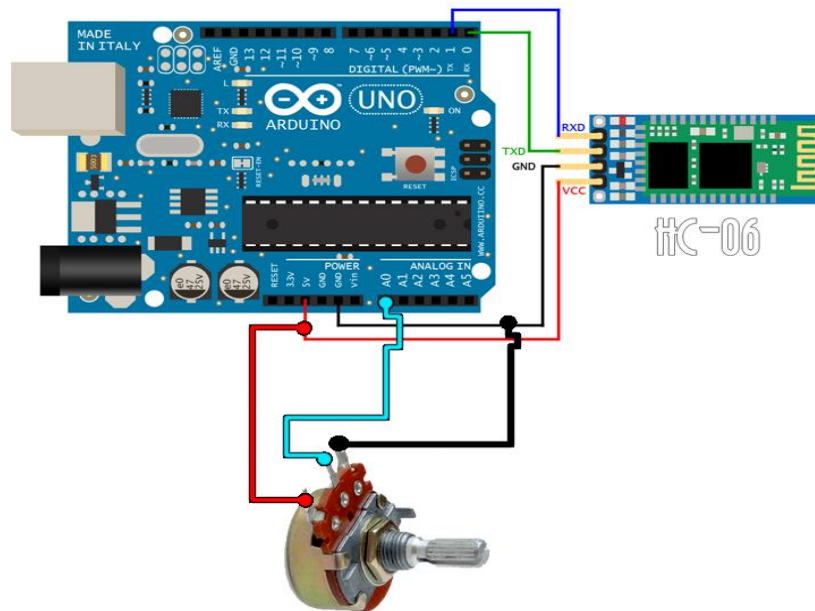


# POTENTIOMETER



## Code ARDUINO :

```
long PortPotentiometre=A0;

float valeur;

void setup() {

  Serial.begin(9600);

}

void loop() {

  if(Serial.available(>0){

    valeur=analogRead(PortPotentiometre);

    valeur=valeur*5/1023;

    Serial.print(valeur);

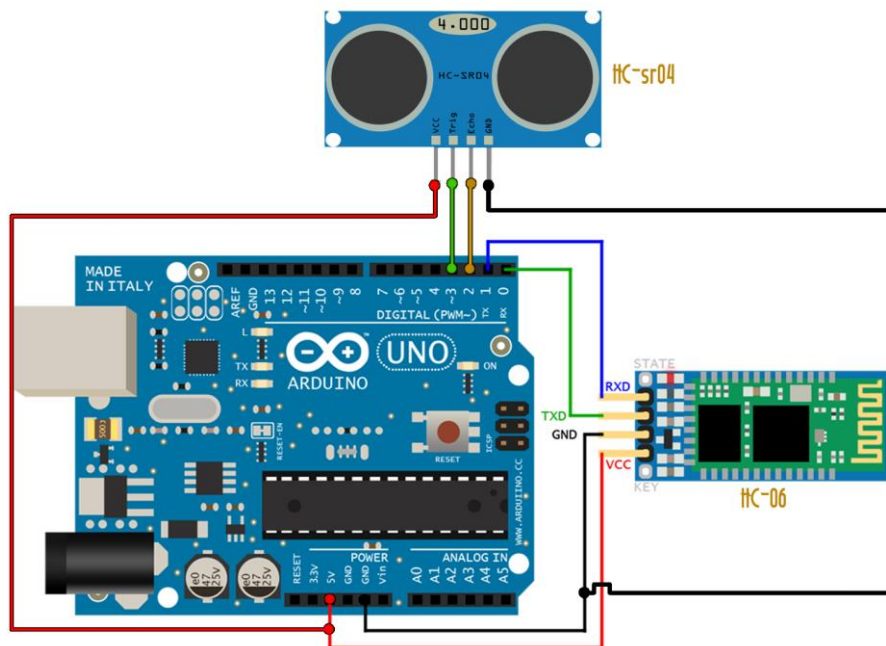
    Serial.print(";");

  }

  delay(1);

}
```

# ULTRASONOR



## Code ARDUINO :

```
char DouTTrigger=3;

char DinEcho=2;

int distance;

void setup() {

  pinMode(DouTTrigger,OUTPUT);

  pinMode(DinEcho,INPUT);

  Serial.begin(9600);

}

void loop() {

  if(Serial.available(>0){

    digitalWrite(DouTTrigger,LOW);

    delayMicroseconds(2);

    digitalWrite(DouTTrigger,HIGH);

    delayMicroseconds(10);
```

```

digitalWrite(DoutTrigger,LOW);

distance=pulseIn(DinEcho,HIGH)/58.0;

Serial.print(";");

Serial.print("0");

Serial.print(distance);

Serial.print(" ");

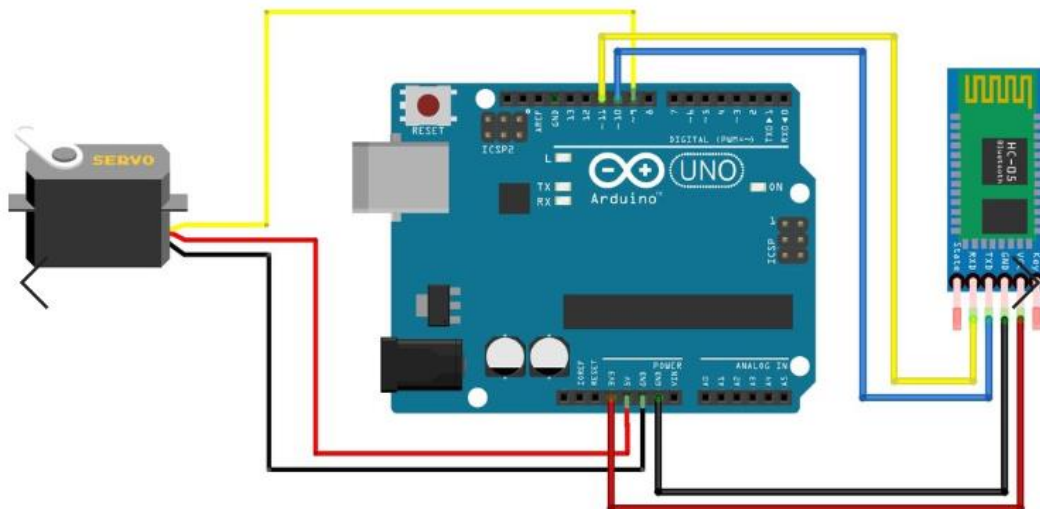
}

delay(1);

}

```

## SEROMOTOR



### Code ARDUINO :

```

#include <Servo.h>    //on inclut la bibliothèque pour piloter un servomoteur

Servo monServo;

int recieverData;

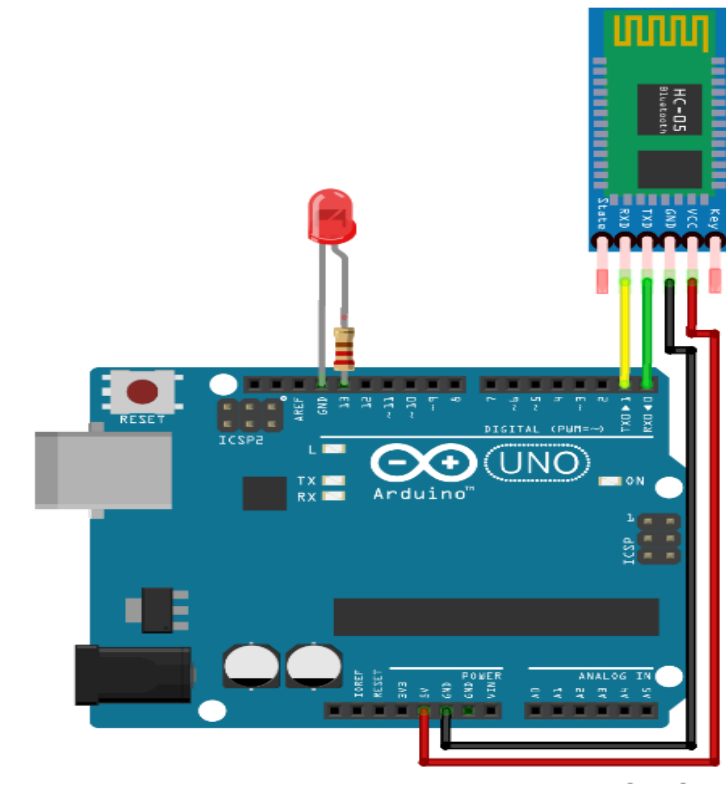
void setup() {

    monServo.attach(9); //on définit le Pin utilisé par le servomoteur

```

```
Serial.begin(9600);  
  
}  
  
void loop() {  
  if(Serial.available()>0){  
    recieverData=Serial.read();  
    monServo.write(recieverData);  
  }  
}
```

## LED



```
byte reciverData;  
  
int led=13;  
  
void setup() {  
  Serial.begin(9600);  
}  
  
void loop() {  
  if(Serial.available()>0){  
    recciverData=Serial.read();  
  
    if(reciverData ==1){  
      digitalWrite(led,HIGH);  
    }else if(reciverData ==0){  
      digitalWrite(led,LOW);  
    } } delay(1);}
```