A red circuit board with many different components

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//Autonomous Car Project

//Motor Control Script

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//29.05.2024

//Arduino Uno Rev3

//Setup variables for the speed pins

int leftSpeedPin = 10; //ENA

int rightSpeedPin = 5; //ENB

//Setup variables for the direction

int leftCwPin = 9; //IN1

int leftCcwPin = 8; //IN2

int rightCwPin = 7; //IN3

int rightCcwPin = 6; //IN4

void setup() {

//Set Pin Modes to Output or Input

pinMode(leftSpeedPin, OUTPUT);

pinMode(rightSpeedPin, OUTPUT);

pinMode(leftCwPin, OUTPUT);

pinMode(leftCcwPin, OUTPUT);

pinMode(rightCwPin, OUTPUT);

pinMode(rightCcwPin, OUTPUT);

}

void loop() {

forwards(200);

delay(100);

left(150);

delay(100);

forwards(200);

delay(100);

right(150);

delay(100);

}

void forwards(int speed){

//Left Clockwise

digitalWrite(leftCwPin, HIGH);

digitalWrite(leftCcwPin, LOW);

//Right Clockwise

digitalWrite(rightCwPin, HIGH);

digitalWrite(rightCcwPin, LOW);

//Output Speed

analogWrite(leftSpeedPin, speed);

analogWrite(rightSpeedPin, speed);

}

void backwards(int speed){

//Left Counter-Clockwise

digitalWrite(leftCwPin, LOW);

digitalWrite(leftCcwPin, HIGH);

//Right Counter-Clockwise

digitalWrite(rightCwPin, LOW);

digitalWrite(rightCcwPin, HIGH);

//Output Speed

analogWrite(leftSpeedPin, speed);

analogWrite(rightSpeedPin, speed);

}

void left(int speed){

//Left Counter-Clockwise

digitalWrite(leftCwPin, LOW);

digitalWrite(leftCcwPin, HIGH);

//Right Clockwise

digitalWrite(rightCwPin, HIGH);

digitalWrite(rightCcwPin, LOW);

//Output Speed

analogWrite(leftSpeedPin, speed);

analogWrite(rightSpeedPin, speed);

}

void right(int speed){

//Left Clockwise

digitalWrite(leftCwPin, HIGH);

digitalWrite(leftCcwPin, LOW);

//Right Counter-Clockwise

digitalWrite(rightCwPin, LOW);

digitalWrite(rightCcwPin, HIGH);

//Output Speed

analogWrite(leftSpeedPin, speed);

analogWrite(rightSpeedPin, speed);

}

void stop(){

analogWrite(leftSpeedPin, 0);

analogWrite(rightSpeedPin, 0);

}