

Student Name	G K Vignesh
Assignment	4

Code:

```
#include <WiFi.h>
#include <PubSubClient.h>
WiFiClient wifiClient;
String data3;
#define ORG "4yi0vc"
#define DEVICE_TYPE "nodeMcu"
#define DEVICE_ID "Assignment4"
#define TOKEN "123456789"
#define speed 0.034
#define led 14
char server[] = ORG ".messaging.internetofthings.ibmcloud.com";
char publishTopic[] = "iot-2/evt/Data/fmt/json";
char topic[] = "iot-2/cmd/home/fmt/String";
char authMethod[] = "use-token-auth";
char token[] = TOKEN;
char clientId[] = "d:" ORG ":" DEVICE_TYPE ":" DEVICE_ID;
PubSubClient client(server, 1883, wifiClient);
void publishData();
```

```
const int trigpin=5;
const int echopin=18;
String command;
String data="";
```

```
long duration;
float dist;
```

```
void setup()
{
  Serial.begin(115200);
  pinMode(led, OUTPUT);
  pinMode(trigpin, OUTPUT);
  pinMode(echopin, INPUT);
  wifiConnect();
  mqttConnect();
```

```

}

void loop() {
  bool isNearby = dist < 100;
  digitalWrite(led, isNearby);

  publishData();
  delay(500);

  if (!client.loop()) {
    mqttConnect();
  }
}

void wifiConnect() {
  Serial.print("Connecting to "); Serial.print("Wifi");
  WiFi.begin("Wokwi-GUEST", "", 6);
  while (WiFi.status() != WL_CONNECTED) {
    delay(500);
    Serial.print(".");
  }
  Serial.print("WiFi connected, IP address: "); Serial.println(WiFi.localIP());
}

void mqttConnect() {
  if (!client.connected()) {
    Serial.print("Reconnecting MQTT client to "); Serial.println(server);
    while (!client.connect(clientId, authMethod, token)) {
      Serial.print(".");
      delay(500);
    }
    initManagedDevice();
    Serial.println();
  }
}

void initManagedDevice() {
  if (client.subscribe(topic)) {
    // Serial.println(client.subscribe(topic));
    Serial.println("IBM subscribe to cmd OK");
  } else {
    Serial.println("subscribe to cmd FAILED");
  }
}

```

```

void publishData()
{
    digitalWrite(trigpin,LOW);
    digitalWrite(trigpin,HIGH);
    delayMicroseconds(10);
    digitalWrite(trigpin,LOW);
    duration=pulseIn(echopin,HIGH);
    dist=duration*speed/2;
    if(dist<100){
        String payload = "{\"Normal Distance\":\"";
        payload += dist;
        payload += "\"}";

        Serial.print("\n");
        Serial.print("Sending payload: ");
        Serial.println(payload);
        if (client.publish(publishTopic, (char*) payload.c_str())) {
            Serial.println("Publish OK");
        }
    }

    if(dist>101 && dist<111){
        String payload = "{\"Alert distance\":\"";
        payload += dist;
        payload += "\"}";

        Serial.print("\n");
        Serial.print("Sending payload: ");
        Serial.println(payload);
        if(client.publish(publishTopic, (char*) payload.c_str())) {
            Serial.println("Warning crosses 110cm -- it automaticaly of the loop");
            digitalWrite(led,HIGH);
        }else {
            Serial.println("Publish FAILED");
        }
    }

}

}

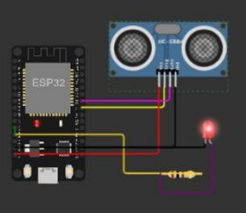
void callback(char* subscribeTopic, byte* payload, unsigned int payloadLength){
    Serial.print("callback invoked for topic:");
    Serial.println(subscribeTopic);
    for(int i=0; i<payloadLength; i++){

```

```
    dist += (char)payload[i];  
  }  
  Serial.println("data:" + data3);  
  if(data3=="lighton"){  
    Serial.println(data3);  
    digitalWrite(led,HIGH);  
  }  
  data3="";  
}
```

Output

Editing Ultrasonic Distance Sensor
Distance: 90cm



Sending payload: {"Normal Distance":89.95}
Publish OK

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Publish OK

Sending payload: {"Normal Distance":89.95}
Publish OK

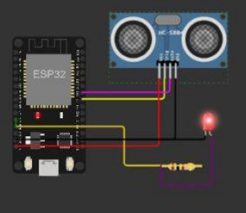
Sending payload: {"Normal Distance":89.98}
Publish OK

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Publish OK

Sending payload: {"Normal Distance":89.95}
Publish OK

**1) when distance under 100 cm
it wil show normal distance**

Editing Ultrasonic Distance Sensor
Distance: 107cm



Sending payload: {"Alert distance":106.98}
Warning crosses 110cm -- it automaticaly of the loop

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Warning crosses 110cm -- it automaticaly of the loop

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Warning crosses 110cm -- it automaticaly of the loop

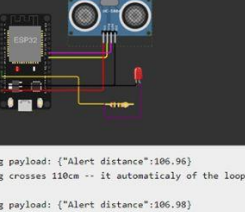
Sending payload: {"Alert distance":106.98}
Warning crosses 110cm -- it automaticaly of the loop

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Sending payload: {"Alert distance":106.98}
Warning crosses 110cm -- it automaticaly of the loop

**2) when distance cross 100 cm
it wil show ALERT with warning message
distance**

Editing Ultrasonic Distance Sensor
Distance: 125cm



Sending payload: {"Alert distance":106.96}
Warning crosses 110cm -- it automaticaly of the loop

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**when it cross above 110 cm it totaly
move to iff state once it reduce to 110 it on again**

IBM CLOUD OUPUT

Recent Events

The recent events listed show the live stream of data that is coming and going from this device.

Event	Value	Format	Last Received
Data	{"Normal Distance":89.95}	json	a few seconds ago
Data	{"Normal Distance":89.95}	json	a few seconds ago
Data	{"Normal Distance":89.95}	json	a few seconds ago
Data	{"Normal Distance":89.95}	json	a few seconds ago
Data	{"Normal Distance":89.95}	json	a few seconds ago

Recent Events

The recent events listed show the live stream of data that is coming and going from this device.

Event	Value	Format	Last Received
Data	{"Alert distance":106.98}	json	a few seconds ago
Data	{"Alert distance":107.03}	json	a few seconds ago
Data	{"Alert distance":106.98}	json	a few seconds ago
Data	{"Alert distance":106.98}	json	a few seconds ago
Data	{"Alert distance":106.98}	json	a few seconds ago