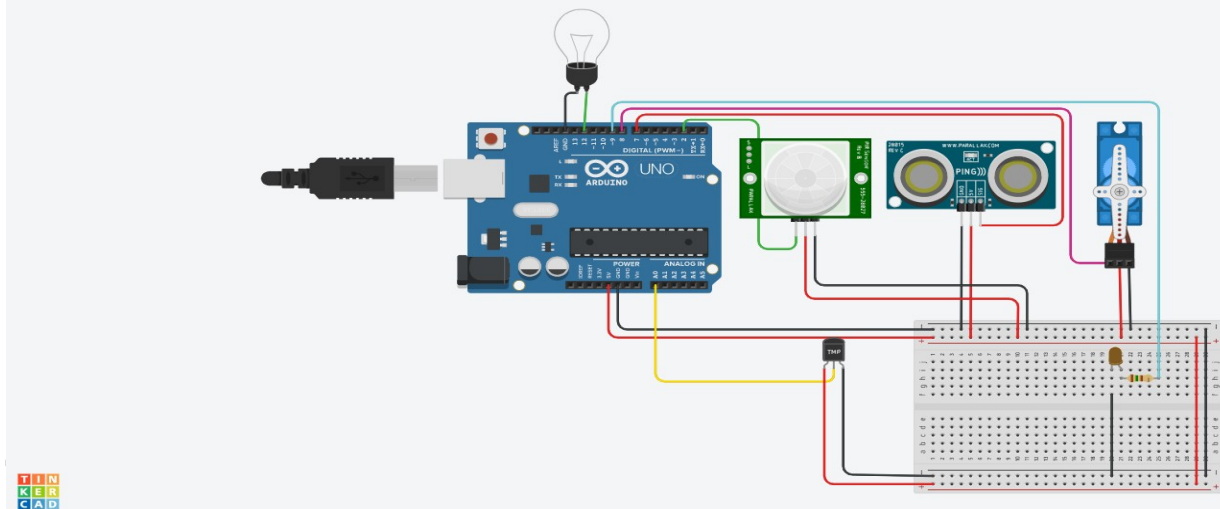


HOME AUTOMATION ASSIGNMENT-1

NAME:SWETHA.s

ROLLNO:113119UG03107



```
#include<Servo.h>int
dist=0;
longreadUltrasonicDistance(inttriggerPin,intechoPin)
{
    pinMode(triggerPin, OUTPUT); /Clear the
    triggerdigitalWrite(triggerPin,
    LOW);delayMicroseconds(2);
    /SetsthetriggertoHIGHstatefor10microsecondsdigitalWrite(triggerPin,
    HIGH);
    delayMicroseconds(10);digit
    alWrite(triggerPin,
```

```
LOW);pinMode(echoPin,INP  
UT);  
/Readstheechopin,andreturnsthesoundwavetraveltimeinmicroseconds  
returnpulseIn(echoPin,HIGH);  
}
```

```

Servo servo_8;
void
setup()
{
  servo_8.attach(8,500,2500);
  pinMode(2,
  INPUT);
  pinMode(12,
  OUTPUT);
  pinMode(A0,
  INPUT);
  pinMode(9,OUTPUT);
}

void loop()
{
  dist=0.01723*readUltrasonicDistance(7,7);
  if(dist<=100){
    servo_8.write(90);
    delay(1000); //Wait for 1000 millisecond(s)
  } else
  {
    servo_8.write(0);
    delay(1000); //Wait for 1000 millisecond(s)
  }
  if(digitalRead(2)==1){
    digitalWrite(12,HIGH);
    delay(1000); //Wait for 1000 millisecond(s)
  } else{
    digitalWrite(12,LOW);
    delay(1000); //Wait for 1000 millisecond(s)
  }
}

```

```
if(analogRead(A0)>200){digi  
  talWrite(9,HIGH);  
  delay(1000);/Waitfor1000millisecond(s)  
}else{  
  digitalWrite(9,LOW);  
  delay(1000);/Waitfor1000millisecond(s)  
}  
}
```

https://www.tinkercad.com/things/krtlmxuR6J8-amazing-kup-hillar/editel?sharecode=jcrNdSyYnQj2Qmt_QlIGcfaduHq8SmRNLxEmXrie-Jg