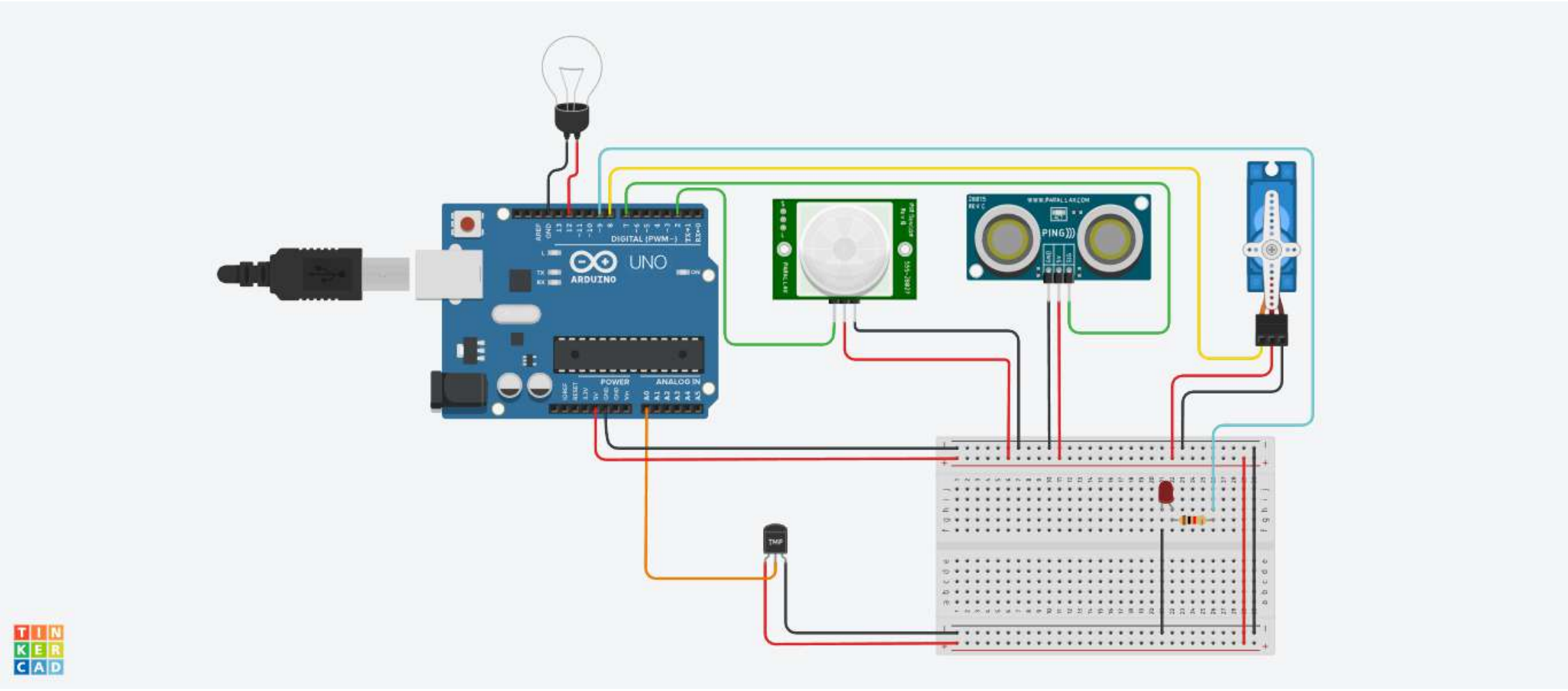

https://www.tinkercad.com/things/bkdHNBgl8ls-frantic-uusam-wolt/editel

```
// C++ code
//
#include <Servo.h>


int set = 0;


int set_to = 0;


int dist = 0;


int read_digital = 0;


int read_digital_pin2 = 0;


long readUltrasonicDistance(int triggerPin, int echoPin)
{
  pinMode(triggerPin, OUTPUT);  // Clear the trigger
  digitalWrite(triggerPin, LOW);
  delayMicroseconds(2);
  // Sets the trigger pin to HIGH state for 10 microseconds
  digitalWrite(triggerPin, HIGH);
  delayMicroseconds(10);
  digitalWrite(triggerPin, LOW);
  pinMode(echoPin, INPUT);
  // Reads the echo pin, and returns the sound wave travel time in microseconds
```

```
  return pulseIn(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) {
  digitalWrite(9, HIGH);
  delay(1000); // Wait for 1000 millisecond(s)
 } else {
  digitalWrite(9, LOW);
  delay(1000); // Wait for 1000 millisecond(s)
 }
}
```