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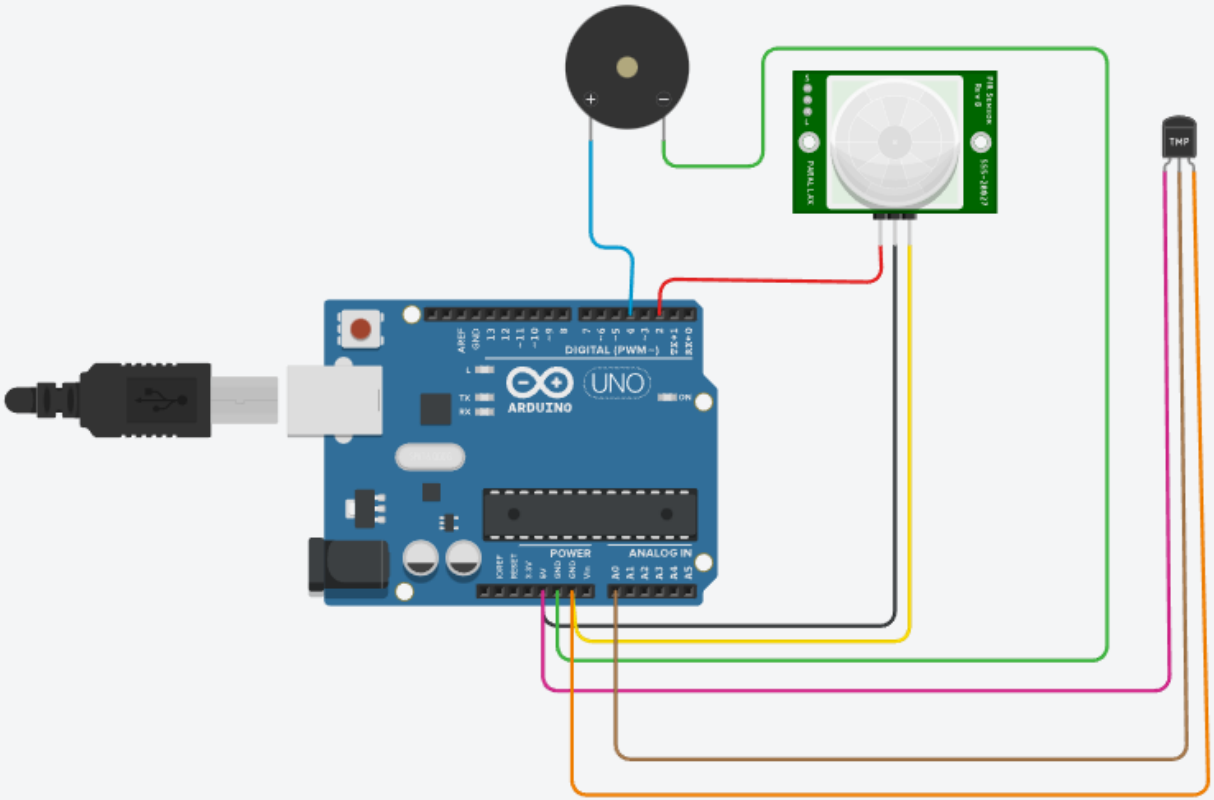

Components
Basic

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Vibration Motor
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Temperature Sensor...
Multimeter

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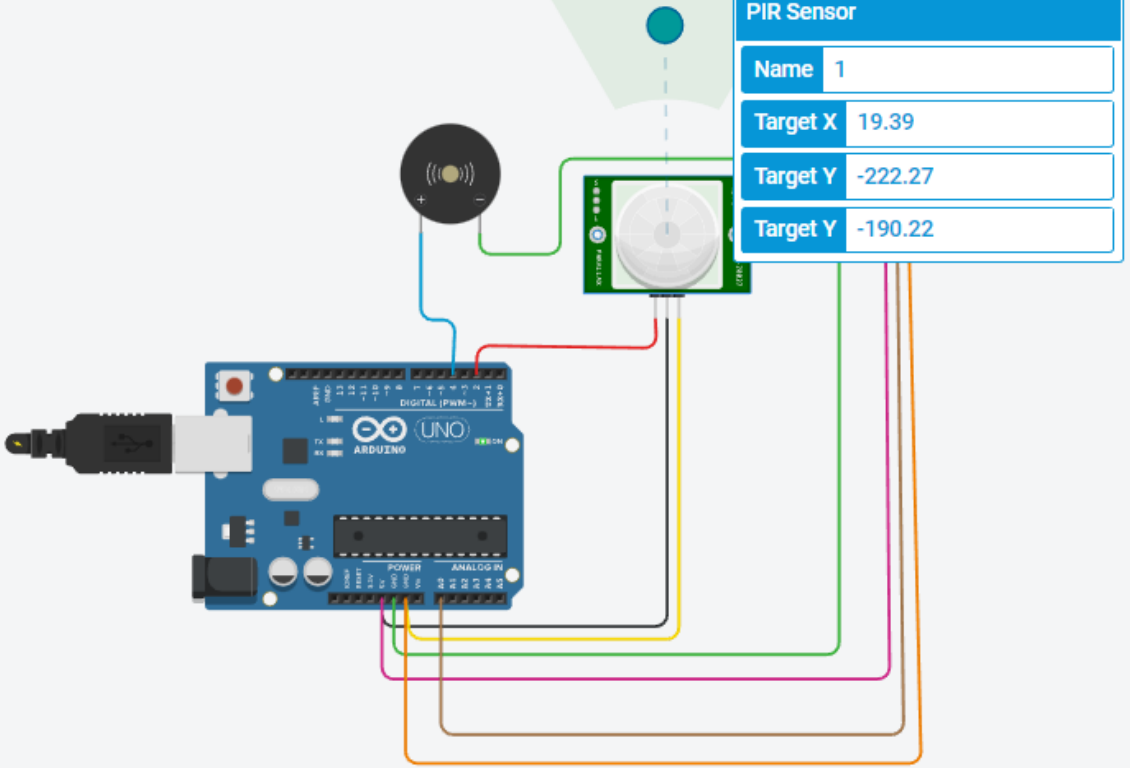

1 (Arduino Uno R3)

```
1
2  int Buzz= 4; //  Buzzer (+ive) pin
3  int PIR= 2; //  PIR pin
4  int val= 0; // Initializing the value as zero at the beginning
5  int temppin=A0;
6  float temp=0;
7
8  void setup() {
9
10 pinMode(Buzz, OUTPUT);
11 pinMode(PIR, INPUT);
12 Serial.begin(9600);
13 }
14
15 void loop() {
16   // code for PIR sensor
17
18 val = digitalRead(PIR); // The value read from PIR pin 3 will be
19 if(val == 1){
20
```

Serial Monitor

```
Movement not Detected
74.71
Movement not Detected
74.71
Movement Detected
74.71
Movement Detected
74.71
```

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Screenshot (7).pdf

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Temperature Sensor [TMP36]

Name 2

1 (Arduino Uno R3)

```
int Buzz= 4; //  Buzzer (+ive) pin
int PIR= 2; //  PIR pin
int val= 0; // Initializing the value as zero at the beginning
int temppin=A0;
float temp=0;

void setup() {

pinMode(Buzz, OUTPUT);
pinMode(PIR, INPUT);
Serial.begin(9600);
}

void loop() {
  // code for PIR sensor

val = digitalRead(PIR); // The value read from PIR pin 3 will be
if(val == 1){
```

Serial Monitor

```
74.71
Movement not Detected
74.71
Movement not Detected
74.71
Movement not Detected
74.71
Movement no
```

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Screenshot (7).pdf

Show all

frantic_bombul_krunk1.ino - Notepad

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```
int Buzz= 4; //  Buzzer (+ive) pin
int PIR= 2; //  PIR pin
int val= 0; // Initializing the value as zero at the beginning
int temppin=A0;
float temp=0;

void setup() {

pinMode(Buzz, OUTPUT);
pinMode(PIR, INPUT);
Serial.begin(9600);
}

void loop() {
  // code for PIR sensor

val = digitalRead(PIR); // The value read from PIR pin 3 will be assigned to 'val'
if(val == 1){
  digitalWrite(Buzz, HIGH); // Turn Buzzer ON
  Serial.println("Movement Detected"); // Print this text in Serial Monitor
}
else
{
 digitalWrite(Buzz, LOW);
  Serial.println("Movement not Detected");
}

  //code for temp sensor

temp=analogRead(temppin);
temp=temp*0.48828125; //or 0.5
Serial.println(temp);
delay(1000);
if (temp>60)
{digitalWrite(Buzz,HIGH);}
else
{digitalWrite (Buzz,LOW);}
}
```

Unix (LF) Ln 1, Col 1 100%