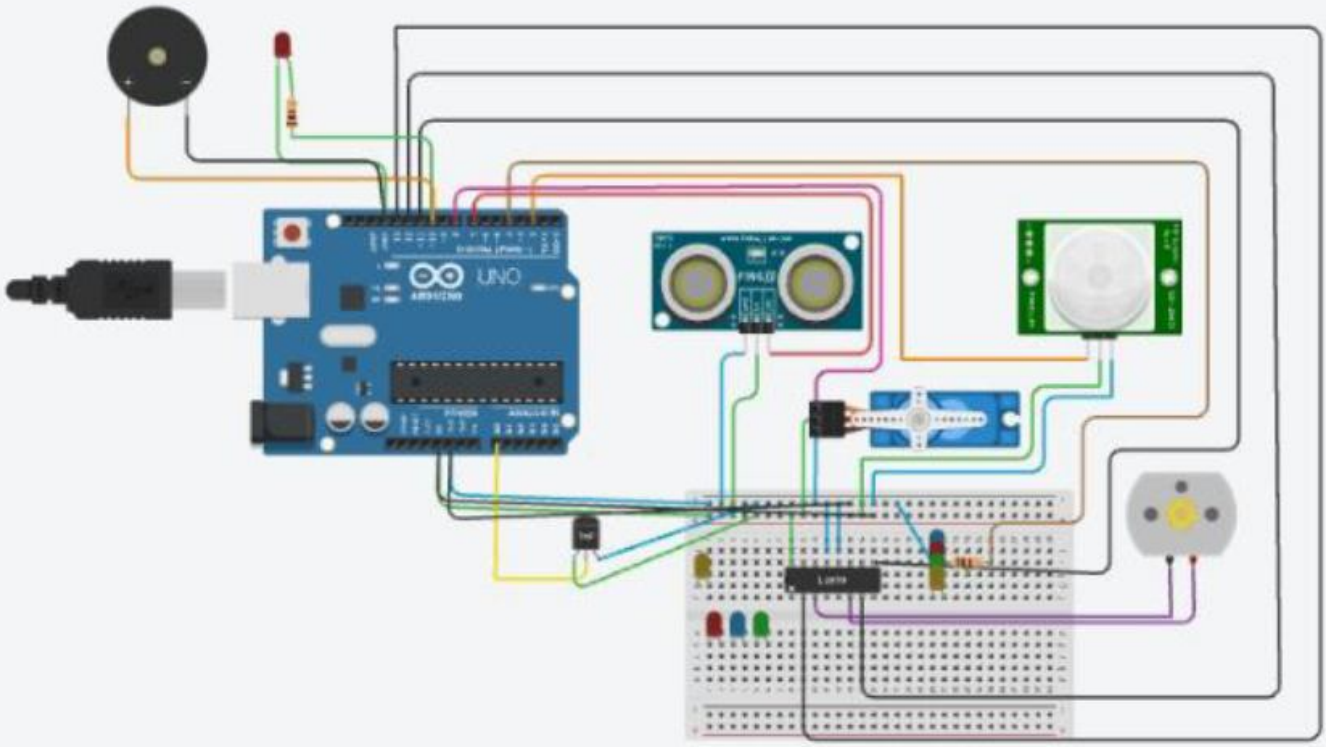
UNO

```
#include<Servo.h>
const int pingPin = 7;
int servoPin = 8;

Servo servo1;

void setup() {
  // initialize serial communication:
  Serial.begin(9600);
  servo1.attach(servoPin);
  pinMode(2,INPUT);
  pinMode(4,OUTPUT);
  pinMode(11,OUTPUT);
  pinMode(12,OUTPUT);
  pinMode(13,OUTPUT);
  pinMode(A0,INPUT);
  digitalWrite(2,LOW);
  digitalWrite(11,HIGH);
   pinMode(2, INPUT);
  pinMode(10,OUTPUT);
}

void loop() {

  long duration, inches, cm;

  pinMode(pingPin, OUTPUT);
  digitalWrite(pingPin, LOW);
  delayMicroseconds(2);
  digitalWrite(pingPin, HIGH);
  delayMicroseconds(5);
  digitalWrite(pingPin, LOW);

  // The same pin is used to read the signal from the PING))): a H
  // whose duration is the time (in microseconds) from the sending
  // to the reception of its echo off of an object.
  pinMode(pingPin, INPUT);
  duration = pulseIn(pingPin, HIGH);

  // convert the time into a distance
  inches = microsecondsToInches(duration);
  cm = microsecondsToCentimeters(duration);

  //Serial.print(inches);
  //Serial.print("in, ");
  //Serial.print(cm);
  //Serial.print("cm");
  //Serial.println();
  //delay(100);

  servo1.write(0);

  if(cm < 40)
  {
    servo1.write(90);
    delay(2000);
  }
  else
  {
    servo1.write(0);
  }

  // PIR with LED starts
  int pir = digitalRead(2);

  if(pir == HIGH)
  {
    digitalWrite(4,HIGH);
    delay(1000);
  }
  else if(pir == LOW)
  {
    digitalWrite(4,LOW);
  }
  //burglar alarm
  Serial.println(digitalRead(2));
  if (digitalRead(2) == 1) {
    digitalWrite(10, HIGH);
  } else {
    digitalWrite(10, LOW);
  }
  delay(10);

  //temp with fan
  float value=analogRead(A0);
  float temperature=value*0.48;

  Serial.println("temperature");
  Serial.println(temperature);

  if(temperature > 20)
  {
    digitalWrite(12,HIGH);
    digitalWrite(13,LOW);
  }
  else
  {
    digitalWrite(12,LOW);
    digitalWrite(13,LOW);
  }
```