

Name: KANIMOZHI.M

Roll NO: 19EC09

ASSIGNMENT 1

SOURCE CODE:

```
#include <Servo.h>

int output1Value = 0;
int sen1Value = 0;
int sen2Value = 0;
int const gas_sensor = A1;
int const LDR = A0;
int limit = 400;

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_7;

void setup()
{
```

```

    Serial.begin(9600);           //initialize serial communication
    pinMode(A0, INPUT);          //LDR
    pinMode(A1, INPUT);          //gas sensor
    pinMode(13, OUTPUT);          //connected to relay
    servo_7.attach(7, 500, 2500); //servo motor

    pinMode(8, OUTPUT);          //signal to piezo buzzer
    pinMode(9, INPUT);           //signal to PIR
    pinMode(10, OUTPUT);          //signal to npn as switch
    pinMode(4, OUTPUT);           //Red LED
    pinMode(3, OUTPUT);           //Green LED

}

void loop()
{

    //-----light intensity control-----//
    //-----
    int val1 = analogRead(LDR);
    if (val1 > 500)
    {
        digitalWrite(13, LOW);
        Serial.print("Bulb ON = ");
        Serial.print(val1);
    }
    else
    {
        digitalWrite(13, HIGH);
        Serial.print("Bulb OFF = ");
        Serial.print(val1);
    }
}

```

```

//-----
//----- light & fan control -----//
//-----

sen2Value = digitalRead(9);
if (sen2Value == 0)
{
    digitalWrite(10, LOW); //npn as switch OFF
    digitalWrite(4, HIGH); // Red LED ON, indicating no motion
    digitalWrite(3, LOW); //Green LED OFF, since no Motion detected
    Serial.print("    || NO Motion Detected  ");
}

if (sen2Value == 1)
{
    digitalWrite(10, HIGH); //npn as switch ON
    delay(3000);
    digitalWrite(4, LOW); // RED LED OFF
    digitalWrite(3, HIGH); //GREEN LED ON , indicating motion detected
    Serial.print("        || Motion Detected!  ");
}
delay(300);

//-----
// ----- Gas Sensor -----//
//-----

int val = analogRead(gas_sensor); //read sensor value
Serial.print("|| Gas Sensor Value = ");
Serial.print(val); //Printing in serial monitor
//val = map(val, 300, 750, 0, 100);
if (val > limit)
{

```

```

        tone(8, 650);
    }
    delay(300);
    noTone(8);

//-----

    //----- servo motor -----//

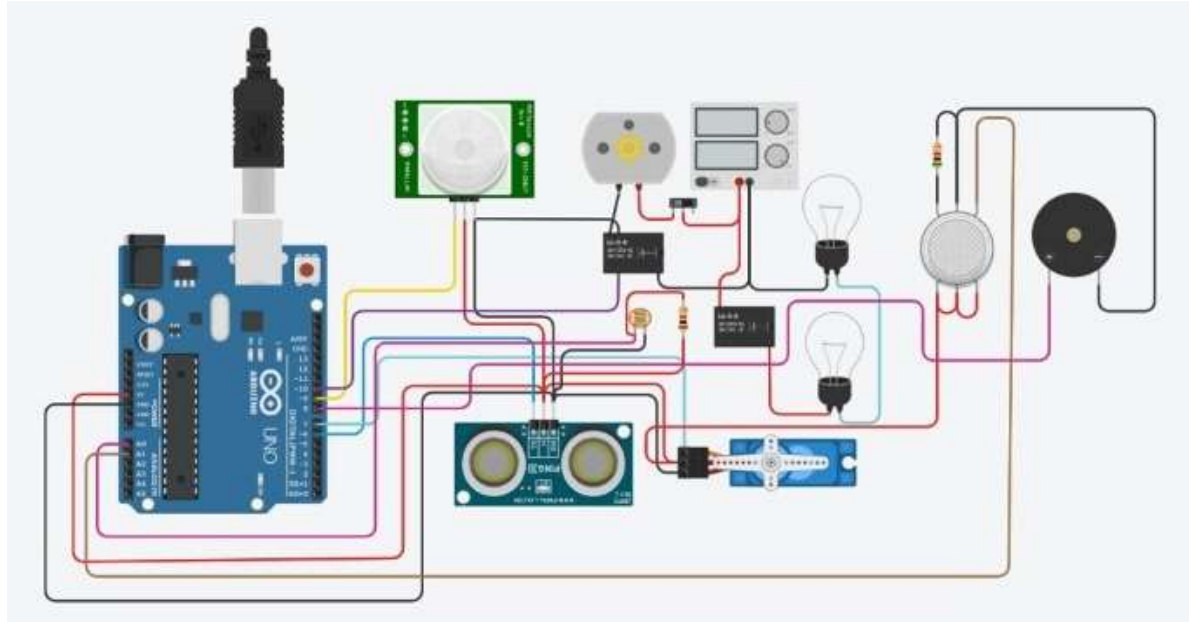
//-----

    sen1Value = 0.01723 * readUltrasonicDistance(6, 6);

    if (sen1Value < 100)
    {
        servo_7.write(90);
        Serial.print("  || Door Open! ; Distance = ");
        Serial.print(sen1Value);
        Serial.print("\n");

    }
    else
    {
        servo_7.write(0);
        Serial.print("  || Door Closed! ; Distance = ");
        Serial.print(sen1Value);
        Serial.print("\n");
    }
    delay(10); // Delay a little bit to improve simulation performance
}

```



Name:HARINI.N

Roll NO: 19EC07

ASSIGNMENT 1

SOURCE CODE:

```
#include <Servo.h>

int output1Value = 0;
int sen1Value = 0;
int sen2Value = 0;
int const gas_sensor = A1;
int const LDR = A0;
int limit = 400;

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_7;

void setup()
{
```

```

    Serial.begin(9600);           //initialize serial communication
    pinMode(A0, INPUT);          //LDR
    pinMode(A1, INPUT);          //gas sensor
    pinMode(13, OUTPUT);         //connected to relay
    servo_7.attach(7, 500, 2500); //servo motor

    pinMode(8, OUTPUT);          //signal to piezo buzzer
    pinMode(9, INPUT);           //signal to PIR
    pinMode(10, OUTPUT);         //signal to npn as switch
    pinMode(4, OUTPUT);          //Red LED
    pinMode(3, OUTPUT);          //Green LED

}

void loop()
{

    //-----light intensity control-----//
    //-----
    int val1 = analogRead(LDR);
    if (val1 > 500)
    {
        digitalWrite(13, LOW);
        Serial.print("Bulb ON = ");
        Serial.print(val1);
    }
    else
    {
        digitalWrite(13, HIGH);
        Serial.print("Bulb OFF = ");
        Serial.print(val1);
    }
}

```

```

//-----
//----- light & fan control -----//
//-----

sen2Value = digitalRead(9);
if (sen2Value == 0)
{
    digitalWrite(10, LOW); //npn as switch OFF
    digitalWrite(4, HIGH); // Red LED ON, indicating no motion
    digitalWrite(3, LOW); //Green LED OFF, since no Motion detected
    Serial.print("    || NO Motion Detected    ");
}

if (sen2Value == 1)
{
    digitalWrite(10, HIGH); //npn as switch ON
    delay(3000);
    digitalWrite(4, LOW); // RED LED OFF
    digitalWrite(3, HIGH); //GREEN LED ON , indicating motion detected
    Serial.print("        || Motion Detected!    ");
}
delay(300);

//-----
// ----- Gas Sensor -----//
//-----

int val = analogRead(gas_sensor); //read sensor value
Serial.print("|| Gas Sensor Value = ");
Serial.print(val); //Printing in serial monitor
//val = map(val, 300, 750, 0, 100);
if (val > limit)
{

```



```

        tone(8, 650);
    }
    delay(300);
    noTone(8);

//-----

    //----- servo motor -----//

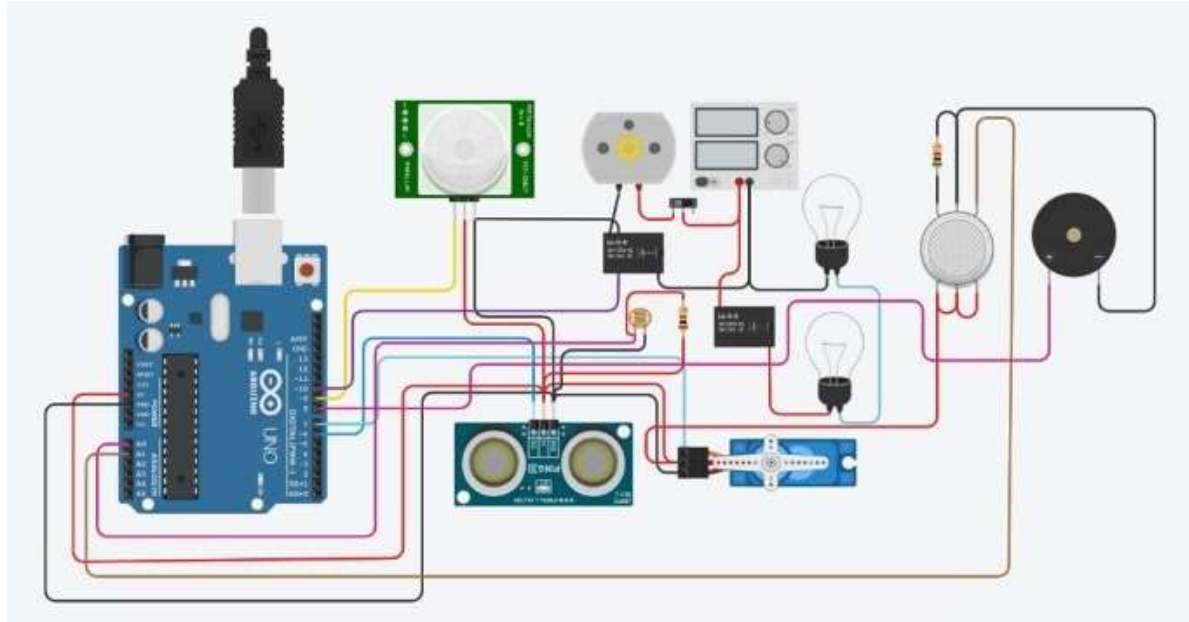
//-----

    sen1Value = 0.01723 * readUltrasonicDistance(6, 6);

    if (sen1Value < 100)
    {
        servo_7.write(90);
        Serial.print("  || Door Open! ; Distance = ");
        Serial.print(sen1Value);
        Serial.print("\n");

    }
    else
    {
        servo_7.write(0);
        Serial.print("  || Door Closed! ; Distance = ");
        Serial.print(sen1Value);
        Serial.print("\n");
    }
    delay(10); // Delay a little bit to improve simulation performance
}

```



Name: KANAGA.E

Roll NO: 19EC08

ASSIGNMENT 1

SOURCE CODE:

```
#include <Servo.h>

int output1Value = 0;
int sen1Value = 0;
int sen2Value = 0;
int const gas_sensor = A1;
int const LDR = A0;
int limit = 400;

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_7;

void setup()
{
```

```

    Serial.begin(9600);           //initialize serial communication
    pinMode(A0, INPUT);          //LDR
    pinMode(A1, INPUT);          //gas sensor
    pinMode(13, OUTPUT);          //connected to relay
    servo_7.attach(7, 500, 2500); //servo motor

    pinMode(8, OUTPUT);          //signal to piezo buzzer
    pinMode(9, INPUT);           //signal to PIR
    pinMode(10, OUTPUT);         //signal to npn as switch
    pinMode(4, OUTPUT);          //Red LED
    pinMode(3, OUTPUT);          //Green LED

}

void loop()
{

    //-----light intensity control-----//
    //-----
    int val1 = analogRead(LDR);
    if (val1 > 500)
    {
        digitalWrite(13, LOW);
        Serial.print("Bulb ON = ");
        Serial.print(val1);
    }
    else
    {
        digitalWrite(13, HIGH);
        Serial.print("Bulb OFF = ");
        Serial.print(val1);
    }
}

```

```

//-----
//----- light & fan control -----//
//-----

sen2Value = digitalRead(9);
if (sen2Value == 0)
{
    digitalWrite(10, LOW); //npn as switch OFF
    digitalWrite(4, HIGH); // Red LED ON, indicating no motion
    digitalWrite(3, LOW); //Green LED OFF, since no Motion detected
    Serial.print("    || NO Motion Detected  ");
}

if (sen2Value == 1)
{
    digitalWrite(10, HIGH); //npn as switch ON
    delay(3000);
    digitalWrite(4, LOW); // RED LED OFF
    digitalWrite(3, HIGH); //GREEN LED ON , indicating motion detected
    Serial.print("        || Motion Detected!  ");
}
delay(300);

//-----
// ----- Gas Sensor -----//
//-----

int val = analogRead(gas_sensor); //read sensor value
Serial.print("|| Gas Sensor Value = ");
Serial.print(val); //Printing in serial monitor
//val = map(val, 300, 750, 0, 100);
if (val > limit)
{

```

```

        tone(8, 650);
    }
    delay(300);
    noTone(8);

//-----

    //----- servo motor -----//

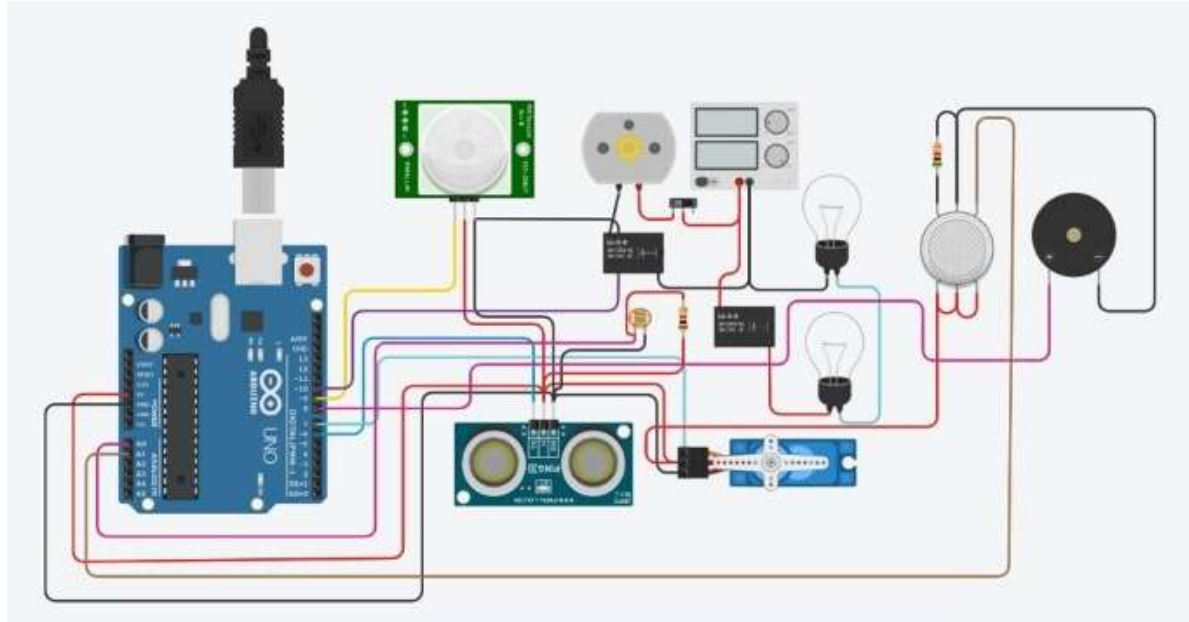
//-----

    sen1Value = 0.01723 * readUltrasonicDistance(6, 6);

    if (sen1Value < 100)
    {
        servo_7.write(90);
        Serial.print("  || Door Open! ; Distance = ");
        Serial.print(sen1Value);
        Serial.print("\n");

    }
    else
    {
        servo_7.write(0);
        Serial.print("  || Door Closed! ; Distance = ");
        Serial.print(sen1Value);
        Serial.print("\n");
    }
    delay(10); // Delay a little bit to improve simulation performance
}

```



Name: PREETHIKA S

Roll NO: 19EC14

ASSIGNMENT 1

SOURCE CODE:

```
#include <Servo.h>

int output1Value = 0;
int sen1Value = 0;
int sen2Value = 0;
int const gas_sensor = A1;
int const LDR = A0;
int limit = 400;

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_7;

void setup()
{
```



```

    Serial.begin(9600);           //initialize serial communication
    pinMode(A0, INPUT);          //LDR
    pinMode(A1, INPUT);          //gas sensor
    pinMode(13, OUTPUT);          //connected to relay
    servo_7.attach(7, 500, 2500); //servo motor

    pinMode(8, OUTPUT);          //signal to piezo buzzer
    pinMode(9, INPUT);           //signal to PIR
    pinMode(10, OUTPUT);         //signal to npn as switch
    pinMode(4, OUTPUT);          //Red LED
    pinMode(3, OUTPUT);          //Green LED

}

void loop()
{

    //-----light intensity control-----//
    //-----
    int val1 = analogRead(LDR);
    if (val1 > 500)
    {
        digitalWrite(13, LOW);
        Serial.print("Bulb ON = ");
        Serial.print(val1);
    }
    else
    {
        digitalWrite(13, HIGH);
        Serial.print("Bulb OFF = ");
        Serial.print(val1);
    }
}

```

```

//-----
//----- light & fan control -----//
//-----

sen2Value = digitalRead(9);
if (sen2Value == 0)
{
    digitalWrite(10, LOW); //npn as switch OFF
    digitalWrite(4, HIGH); // Red LED ON, indicating no motion
    digitalWrite(3, LOW); //Green LED OFF, since no Motion detected
    Serial.print("    || NO Motion Detected    ");
}

if (sen2Value == 1)
{
    digitalWrite(10, HIGH); //npn as switch ON
    delay(3000);
    digitalWrite(4, LOW); // RED LED OFF
    digitalWrite(3, HIGH); //GREEN LED ON , indicating motion detected
    Serial.print("        || Motion Detected!    ");
}
delay(300);

//-----
// ----- Gas Sensor -----//
//-----

int val = analogRead(gas_sensor); //read sensor value
Serial.print("|| Gas Sensor Value = ");
Serial.print(val); //Printing in serial monitor
//val = map(val, 300, 750, 0, 100);
if (val > limit)
{

```

```

        tone(8, 650);
    }
    delay(300);
    noTone(8);

//-----

    //----- servo motor -----//

//-----

    sen1Value = 0.01723 * readUltrasonicDistance(6, 6);

    if (sen1Value < 100)
    {
        servo_7.write(90);
        Serial.print("  || Door Open! ; Distance = ");
        Serial.print(sen1Value);
        Serial.print("\n");

    }
    else
    {
        servo_7.write(0);
        Serial.print("  || Door Closed! ; Distance = ");
        Serial.print(sen1Value);
        Serial.print("\n");
    }
    delay(10); // Delay a little bit to improve simulation performance
}

```

