Sumowar

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#include <AFMotor.h>

AF_DCMotor motor2(2, MOTOR12_64KHZ); // create motor #2, 64KHz pwm
AF_DCMotor motor3(3, MOTOR12_64KHZ); // create motor #2, 64KHz pwm

void setup() {
  motor2.setSpeed(250);     // set the speed to 200/255
  motor3.setSpeed(250);     // set the speed to 200/255
  pinMode(A0, INPUT_PULLUP); // Set pin to High state and an Input
  pinMode(A1, INPUT_PULLUP); // Set pin to High state and an Input
//  delay(3000);  //Chill a bit before motors start
}
void f(int d) { // Call Forward
  motor3.run(FORWARD);     // turn it on going forward
  motor2.run(FORWARD);     // turn it on going forward
  delay(d);
}

void b(int d) { // Call Backup
  motor3.run(BACKWARD);    // the other way
  motor2.run(BACKWARD);    // the other way
  delay(d);
}

void r(int d) { // Call Turn Right
  motor3.run(BACKWARD);     // turn it on going reverse
  motor2.run(FORWARD);     // turn it on going forward
  delay(d);
}

void l(int d) { // Call Turn Left
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  motor3.run(FORWARD);      // turn it on going forward
  motor2.run(BACKWARD);       // turn it on going reverse
  delay(d);
}

void s(int d) { // Call Stop
  motor2.run(RELEASE);      // stopped
  motor3.run(RELEASE);      // stopped
  delay(d);
}

void loop() {
  if (digitalRead(A0) == LOW) {
    b(500); // 1/2 second stop
    r(500); // 1/2 Turn Left
  }
  if (digitalRead(A1) == LOW) {
    b(400); // 1/2 second stop
    l(500); // 1/2 Turn Right
  }

  if (analogRead(A2) > 400) {
    b(300); // 1/2 second stop
    r(400); // 1/2 Turn Right
  }
  if (analogRead(A3) > 400) {
    b(300); // 1/2 second stop
    l(400); // 1/2 Turn Left
  }
  s(10);  // go forward for 10 milliseconds
}
```