// Define motor control pins

#define MOTOR\_A\_FORWARD 32 // Motor A forward pin

#define MOTOR\_A\_BACKWARD 33 // Motor A backward pin

#define MOTOR\_B\_FORWARD 25 // Motor B forward pin

#define MOTOR\_B\_BACKWARD 26 // Motor B backward pin

void setup() {

// Set motor control pins as outputs

pinMode(MOTOR\_A\_FORWARD, OUTPUT);

pinMode(MOTOR\_A\_BACKWARD, OUTPUT);

pinMode(MOTOR\_B\_FORWARD, OUTPUT);

pinMode(MOTOR\_B\_BACKWARD, OUTPUT);

}

void loop() {

// Move forward

moveForward();

delay(1500); // Move forward for 1.5 seconds

// Stop

stopMotors();

delay(1500); // Stop for 1.5 seconds

// Move forward again

moveForward();

delay(1500); // Move forward for 1.5 seconds

// Stop

stopMotors();

delay(1000); // Stop for 1 second

// Turn left

turnLeft();

delay(1000); // Turn left for 1 second

// Stop

stopMotors();

delay(1000); // Stop for 1 second

// Turn right

turnRight();

delay(1000); // Turn right for 1 second

// Stop

stopMotors();

delay(1000); // Stop for 1 second

}

void moveForward() {

digitalWrite(MOTOR\_A\_FORWARD, HIGH);

digitalWrite(MOTOR\_A\_BACKWARD, LOW);

digitalWrite(MOTOR\_B\_FORWARD, HIGH);

digitalWrite(MOTOR\_B\_BACKWARD, LOW);

}

void turnLeft() {

digitalWrite(MOTOR\_A\_FORWARD, LOW);

digitalWrite(MOTOR\_A\_BACKWARD, LOW);

digitalWrite(MOTOR\_B\_FORWARD, HIGH);

digitalWrite(MOTOR\_B\_BACKWARD, LOW);

}

void turnRight() {

digitalWrite(MOTOR\_A\_FORWARD, HIGH);

digitalWrite(MOTOR\_A\_BACKWARD, LOW);

digitalWrite(MOTOR\_B\_FORWARD, LOW);

digitalWrite(MOTOR\_B\_BACKWARD, LOW);

}

void stopMotors() {

digitalWrite(MOTOR\_A\_FORWARD, LOW);

digitalWrite(MOTOR\_A\_BACKWARD, LOW);

digitalWrite(MOTOR\_B\_FORWARD, LOW);

digitalWrite(MOTOR\_B\_BACKWARD, LOW);

}