“ KAIRO THE WI-FI ROBO USING NODE MCU” code*

```
#define ENA   14
#define ENB   12
#define IN_1  15
#define IN_2  13
#define IN_3  2
#define IN_4  0

#include <ESP8266WiFi.h>
#include <WiFiClient.h>
#include <ESP8266WebServer.h>

String command;
int speedCar = 800;
int speed_Coeff = 3;

const char* ssid = "Harish Projects wifi car";
ESP8266WebServer server(80);

void setup() {

 pinMode(ENA, OUTPUT);
 pinMode(ENB, OUTPUT);
 pinMode(IN_1, OUTPUT);
 pinMode(IN_2, OUTPUT);
 pinMode(IN_3, OUTPUT);
 pinMode(IN_4, OUTPUT);

  Serial.begin(115200);

// Connecting WiFi

  WiFi.mode(WIFI_AP);
  WiFi.softAP(ssid);

  IPAddress myIP = WiFi.softAPIP();
  Serial.print("AP IP address: ");
  Serial.println(myIP);

 // Starting WEB-server
    server.on ( "/", HTTP_handleRoot );
    server.onNotFound ( HTTP_handleRoot );
    server.begin();
}

void goAhead(){

    digitalWrite(IN_1, LOW);
    digitalWrite(IN_2, HIGH);
    analogWrite(ENA, speedCar);

    digitalWrite(IN_3, LOW);
    digitalWrite(IN_4, HIGH);
    analogWrite(ENB, speedCar);
  }

void goBack(){

    digitalWrite(IN_1, HIGH);
    digitalWrite(IN_2, LOW);
    analogWrite(ENA, speedCar);

    digitalWrite(IN_3, HIGH);
    digitalWrite(IN_4, LOW);
    analogWrite(ENB, speedCar);
  }

void goRight(){

    digitalWrite(IN_1, HIGH);
    digitalWrite(IN_2, LOW);
    analogWrite(ENA, speedCar);

    digitalWrite(IN_3, LOW);
    digitalWrite(IN_4, HIGH);
    analogWrite(ENB, speedCar);
  }

void goLeft(){

    digitalWrite(IN_1, LOW);
    digitalWrite(IN_2, HIGH);
    analogWrite(ENA, speedCar);

    digitalWrite(IN_3, HIGH);
    digitalWrite(IN_4, LOW);
    analogWrite(ENB, speedCar);
  }

void goAheadRight(){

    digitalWrite(IN_1, LOW);
    digitalWrite(IN_2, HIGH);
    analogWrite(ENA, speedCar/speed_Coeff);

    digitalWrite(IN_3, LOW);
    digitalWrite(IN_4, HIGH);
    analogWrite(ENB, speedCar);
  }

void goAheadLeft(){

    digitalWrite(IN_1, LOW);
```

```
    digitalWrite(IN_2, HIGH);
    analogWrite(ENA, speedCar);

    digitalWrite(IN_3, LOW);
    digitalWrite(IN_4, HIGH);
    analogWrite(ENB, speedCar/speed_Coeff);
  }

void goBackRight(){

    digitalWrite(IN_1, HIGH);
    digitalWrite(IN_2, LOW);
    analogWrite(ENA, speedCar/speed_Coeff);

    digitalWrite(IN_3, HIGH);
    digitalWrite(IN_4, LOW);
    analogWrite(ENB, speedCar);
  }

void goBackLeft(){

    digitalWrite(IN_1, HIGH);
    digitalWrite(IN_2, LOW);
    analogWrite(ENA, speedCar);

    digitalWrite(IN_3, HIGH);
    digitalWrite(IN_4, LOW);
    analogWrite(ENB, speedCar/speed_Coeff);
  }

void stopRobot(){

    digitalWrite(IN_1, LOW);
    digitalWrite(IN_2, LOW);
    analogWrite(ENA, speedCar);

    digitalWrite(IN_3, LOW);
    digitalWrite(IN_4, LOW);
    analogWrite(ENB, speedCar);
 }

void loop() {
   server.handleClient();

    command = server.arg("State");
    if (command == "F") goAhead();
    else if (command == "B") goBack();
    else if (command == "L") goLeft();
    else if (command == "R") goRight();
    else if (command == "I") goAheadRight();
    else if (command == "G") goAheadLeft();
    else if (command == "J") goBackRight();
    else if (command == "H") goBackLeft();
    else if (command == "0") speedCar = 400;
    else if (command == "1") speedCar = 470;
    else if (command == "2") speedCar = 540;
    else if (command == "3") speedCar = 610;
    else if (command == "4") speedCar = 680;
    else if (command == "5") speedCar = 750;
    else if (command == "6") speedCar = 820;
    else if (command == "7") speedCar = 890;
    else if (command == "8") speedCar = 960;
    else if (command == "9") speedCar = 1023;
    else if (command == "S") stopRobot();
}

void HTTP_handleRoot(void) {

if( server.hasArg("State") ){
      Serial.println(server.arg("State"));
  }
  server.send ( 200, "text/html", "" );
  delay(1);
}
```