#include<Wire.h>

#include<LiquidCrystal\_I2C.h>

LiquidCrystal\_I2C lcd(0x27,2,1,0,4,5,6,7,3,POSITIVE);

#define trigPin 3

#define echoPin 2

#define trigPin1 4

#define echoPin1 5

#define motor 7

#define buzzer 6

void setup()

{

pinMode(trigPin, OUTPUT);

pinMode(echoPin, INPUT);

pinMode(trigPin1, OUTPUT);

pinMode(echoPin1, INPUT);

pinMode(motor, OUTPUT);

pinMode(buzzer,OUTPUT);

}

void loop()

{

Serial.begin(9600);

long duration, distance,duration1,distance1;

//SonarSensor(trigPin,echoPin);

//SonarSensor(trigPin1,echoPin1);

digitalWrite(trigPin1, LOW);

delayMicroseconds(2);

digitalWrite(trigPin1, HIGH);

delayMicroseconds(10);

digitalWrite(trigPin1, LOW);

duration1 = pulseIn(echoPin1, HIGH);

distance1 = (duration1/2) / 29.1;

if (distance1 < 70)// This is where checking the distanceyou can change the value

{

digitalWrite(motor,HIGH); // When the the distance below 100cm

digitalWrite(buzzer,HIGH);

lcd.begin(16,2);

lcd.backlight();

lcd.setCursor(0,0);

lcd.print("Help! Contact");

lcd.setCursor(0,1);

lcd.print("No: 9849033541");

}

else

{

digitalWrite(trigPin, LOW);

delayMicroseconds(2);

digitalWrite(trigPin, HIGH);

delayMicroseconds(10);

digitalWrite(trigPin, LOW);

duration = pulseIn(echoPin, HIGH);

distance = (duration/2) / 29.1;

if (distance < 70)// This is where checking the distanceyou can change the value

{

digitalWrite(buzzer,HIGH);

}

else{

digitalWrite(motor,LOW); // When the the distance below 100cm

digitalWrite(buzzer,LOW);

}

}

}