

```
1  #from tkinter import *
2  import RPi.GPIO as GPIO
3  import time
4  #import math
5
6
7  GPIO.setmode (GPIO.BOARD)
8
9  RM_A = 10
10 RM_B = 8
11 LM_A = 3
12 LM_B = 5
13
14 pin_pwm_L = 7
15 pin_pwm_R = 12
16
17 GPIO.setup(RM_A ,GPIO.OUT)
18 GPIO.setup(RM_B,GPIO.OUT)
19 GPIO.setup(LM_A, GPIO.OUT)
20 GPIO.setup(LM_B, GPIO.OUT)
21
22 GPIO.setup(pin_pwm_L,GPIO.OUT)
23 GPIO.setup(pin_pwm_R,GPIO.OUT)
24
25 pwm_L = GPIO.PWM(pin_pwm_L,100)
26 pwm_R = GPIO.PWM(pin_pwm_R,100)
27
28 pwm_L.start(100)
29 pwm_R.start(100)
30
31
32 def leftMotor (velL,delante1):
33     pwm_L.ChangeDutyCycle(velL)
34     if delante1 == 1:
35         GPIO.output(LM_A,True)
36         GPIO.output(LM_B,False)
37
38     else:
39         GPIO.output(LM_A,False)
40         GPIO.output(LM_B,True)
41
42     print(velL)
43
44
45
46
47 def rightMotor (velR, delante2):
48     pwm_R.ChangeDutyCycle(velR)
49     if delante2 == 1:
50         GPIO.output(RM_A,True)
51         GPIO.output(RM_B,False)
52     else:
53         GPIO.output(RM_A,False)
54         GPIO.output(RM_B,True)
55     print (velR)
56
57
58 GPIO.cleanup()
59
```