#include <Servo.h>

Servo myservo; // create servo object to control a servo

// twelve servo objects can be created on most boards

int pos = 0;

void setup() {

// put your setup code here, to run once:

myservo.attach(11);

pinMode(2, OUTPUT);

pinMode(3, OUTPUT);

pinMode(4, OUTPUT);

pinMode(5, OUTPUT);

pinMode(6, OUTPUT);

pinMode(A0, INPUT);

pinMode(A1, INPUT);

pinMode(A2, INPUT);

Serial.begin(9600);

digitalWrite(6, HIGH);

}

void loop() {

// put your main code here, to run repeatedly:

int a = analogRead(A0);

int b = analogRead(A1);

int c = analogRead(A2);

Serial.print(a);

Serial.print(" ");

Serial.print(b);

Serial.print(" ");

Serial.print(c);

Serial.println(" ");

delay(50);

if (a<=250)

{

digitalWrite(2, LOW);

digitalWrite(3, LOW);

digitalWrite(4, LOW);

digitalWrite(5, LOW);

digitalWrite(6, LOW);

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

//delay(200);

}

else if(b<=450)

{

digitalWrite(2, LOW);

digitalWrite(3, LOW);

digitalWrite(4, LOW);

digitalWrite(5, LOW);

digitalWrite(6, LOW);

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

}

else if(c<=250)

{

digitalWrite(2, LOW);

digitalWrite(3, LOW);

digitalWrite(4, LOW);

digitalWrite(5, LOW);

digitalWrite(6, LOW);

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 60; pos <= 120; pos += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

for (pos = 120; pos >= 60; pos -= 1) { // goes from 180 degrees to 0 degrees

myservo.write(pos); // tell servo to go to position in variable 'pos'

delay(15); // waits 15 ms for the servo to reach the position

}

}

else if(a>=251 && a<=700)

{

digitalWrite(6, HIGH);

digitalWrite(2, LOW);

digitalWrite(3,HIGH);

digitalWrite(4, HIGH);

digitalWrite(5, LOW);

delay(500);

digitalWrite(6, HIGH);

digitalWrite(2, HIGH);

digitalWrite(3, LOW);

digitalWrite(4, HIGH);

digitalWrite(5, LOW);

delay(500);

}

else if(b>=251 && b<=800)

{

digitalWrite(2, LOW);

digitalWrite(3,HIGH);

digitalWrite(4, HIGH);

digitalWrite(5, LOW);

digitalWrite(6, HIGH);

}

else if(c>=251 && c<=800)

{

digitalWrite(2, HIGH);

digitalWrite(3, LOW);

digitalWrite(4, LOW);

digitalWrite(5, HIGH);

digitalWrite(6, HIGH);

delay(500);

digitalWrite(6, HIGH);

digitalWrite(2, HIGH);

digitalWrite(3, LOW);

digitalWrite(4, HIGH);

digitalWrite(5, LOW);

delay(500);

}

else

{

digitalWrite(6, HIGH);

digitalWrite(2, HIGH);

digitalWrite(3, LOW);

digitalWrite(4, HIGH);

digitalWrite(5, LOW);

}

}