```
#include <math.h>
#include "Wire.h"
#include "WiiChuck.h"
//================================================================================
int MotorI = 9;
int MotorD = 10;
int Var_y = 0;
int X1 = 0;
int X2 = 0;
int X = 0;
int I = 0;
int D = 0;
int dir1_I = 2;
int dir2_I = 3;
int dir1_D = 4;
int dir2_D = 5;
WiiChuck chuck = WiiChuck();
//================================================================================
void setup() {
	Serial.begin(115200);
	chuck.begin();
	chuck.update();
	chuck.calibrateJoy();
	pinMode(MotorI, OUTPUT);
	pinMode(MotorD, OUTPUT);
}
```

```
//============================================================================

void loop() {

	inicio:

		delay(20);

		chuck.update();

}

//==================Dirección en Y=============================================

Var_y = chuck.readJoyY();

if (Var_y >= -25) {

	Var_y = map(Var_y, -25, 60, 90, 255);

	digitalWrite(dir1_I,HIGH);

	digitalWrite(dir2_I,LOW);

	digitalWrite(dir1_D,HIGH);

	digitalWrite(dir2_D,LOW);

	goto dif_ejes;

}

if (Var_y <= -37) {

	Var_y = map(Var_y, -37, -127, 90, 255);

	digitalWrite(dir1_I,LOW);

	digitalWrite(dir2_I,HIGH);

	digitalWrite(dir1_D,LOW);

	digitalWrite(dir2_D,HIGH);

	goto dif_ejes;

}

I = 0;

D = 0;
```

```
digitalWrite(dir1_I,HIGH);
digitalWrite(dir2_I,LOW);
digitalWrite(dir1_D,HIGH);
digitalWrite(dir2_D,LOW);
goto escribir;
//==================Diferencia ejes=============================================
dif_ejes:
//==================Derecha================================
X = chuck.readJoyX();
if (X >= 137) {
        if (X > 200) {
                I = 255;
                D = 0;
                goto escribir;
        }
        X1 = map(X, 137, 200, 155, 255);
        X2 = (255-X1);
        goto datofinal;
}
//=================Izquierda================================
if (X <= 117) {
        if (X < 40){
                I = 0;
                D = 255;
                goto escribir;
        }
```

```
        X2 = map(X, 117, 40, 155, 255);
        X1 = (255-X2);
        goto datofinal;
}
X1=255;
X2=255;
//=========================================================
datofinal:
        I = (Var_y*X1)/255;
        D = (Var_y*X2)/255;
//=========================================================
escribir:
        analogWrite(MotorI, D);
        analogWrite(MotorD, I);
```