Harry in the Maze

Maze:

In this code, we have left sensor , right sensor , front sensor to check the obstacles around the robot , So we initialize front sensor as high, left and right sensors as low as he suppose that the maze's start has front road and no left or right. In setup function, we just set pinModes , In loop function , the sensors start to take the readings and then we check the robot direction through the maze by this readings by if statements . As in 1st case if he has right and has no left he will always move to the right whatever the front sensor is high or low and if he has no right or front he will move to the left and if he has right and left but no front in 1st time he will move to the left then in 2nd time he will move to the right and all the rest cases he will move forward .

Safe:

In this code , In setup function we connect arduino with three rotrary encoders and then we calculated counter of each encoder . In loop function , we calculated the rotational angle of each encoder and check the conditions of each angle through if statement.