**CODING**

#include <Servo.h>

#include <AFMotor.h>

Servo myservo;

Servo myservo1;

int pos = 90;

int pos1 = 0;

AF\_DCMotor motor (1);

AF\_DCMotor motor1(2);

AF\_DCMotor motor2(3);

AF\_DCMotor motor3(4);

void setup () {

myservo.attach(9);

myservo1.attach(10);

pinMode (0, INPUT);

pinMode (1, INPUT);

pinMode (2, INPUT);

pinMode (13, OUTPUT);

myservo.write(pos);

delay (1000);

myservo1.write(pos1);

digitalWrite(13, LOW);

motor. setSpeed (150);

motor1.setSpeed(150);

motor2.setSpeed(150);

motor3.setSpeed(150);

motor.run(RELEASE);

motor1.run (RELEASE);

motor2.run (RELEASE);

motor3.run (RELEASE);

}

void loop () {

f ();

if( digitalRead(0)==LOW){ //LEFT

r ();

delay (1000);

b ();

delay (1000);

r ();

sl ();

f ();

}

If (digitalRead(1)==LOW){

R ();

delay (1000);

b ();

delay (1000);

r ();

s ();

f ();

}

If ( digitalRead(2)==LOW){

R ();

Delay (1000);

B ();

Delay (1000);

R ();

sr();

f ();

}

}

void sr(){

for (int i=0;i<70;i++){

pos--;

myservo.write(pos);

delay (20);

}

S ();

For (int i=0;i<70;i++){

pos++;

myservo.write(pos);

delay (20);

}

}

void sl(){

for (int i=0;i<70;i++){

pos++;

myservo.write(pos);

delay (20);

}

S ();

For (int i=0;i<70;i++){

pos--;

myservo.write(pos);

delay (20);

}

}

void s(){

for (pos1 = 0; pos1 <= 100; pos1 += 1) { // goes from 0 degrees to 180 degrees

// in steps of 1 degree

myservo1.write(pos1);

delay(20); // waits 15 ms for the servo to reach the position

}

digitalWrite(13,HIGH);

delay(3000);

digitalWrite(13,LOW);

for (pos1 = 100; pos1 >= 0; pos1 -= 1) { // goes from 180 degrees to 0 degrees

myservo1.write(pos1);

delay(20); // waits 15 ms for the servo to reach the position

}

}

void f(){

motor.run (BACKWARD);

motor3.run (BACKWARD);

motor1.run (BACKWARD);

motor2.run (BACKWARD);

}

void b (){

motor.run (FORWARD);

motor3.run (FORWARD);

motor1.run (FORWARD);

motor2.run (FORWARD);

}

void r(){

motor.run (RELEASE);

motor1.run (RELEASE);

motor2.run (RELEASE);

motor3.run (RELEASE);

}

/\*

uint8\_t i;

for(i=0; i<255; i++){

motor.setSpeed(i);

motor1.setSpeed(i);

motor2.setSpeed(i);

motor3.setSpeed(i);

delay(10);

}

for(i=255; i!=0; i--){

motor.setSpeed(i);

motor1.setSpeed(i);

motor2.setSpeed(i);

motor3.setSpeed(i);

delay(10);

}

For (i=0; i<255; i++) {

motor.setSpeed(i);

motor1.setSpeed(i);

motor2.setSpeed(i);

motor3.setSpeed(i);

delay(10);

}

for(i=255; i!=0; i--){

motor.setSpeed(i);

motor1.setSpeed(i);

motor2.setSpeed(i);

motor3.setSpeed(i);

delay(10);

}

\*/