```
#include <LiquidCrystal_I2C.h>
LiquidCrystal_I2C lcd(0x27, 16, 2);
#include<SoftwareSerial.h>
SoftwareSerial rfid(5,1);  //rx,tx
#include <Servo.h>
Servo myservo;
String rcv;
int ir=6;
int ir1=3;
int ir2=4;
int ir3=0;
void setup ()
{
Serial.begin(9600);
 myservo.attach(7);
rfid.begin(9600);
 pinMode(ir,INPUT);
 pinMode(ir1, INPUT);
 pinMode(ir2,INPUT);
 pinMode(ir3, INPUT);
   lcd.init();
  // Turn on the blacklight and print a message.
  lcd.backlight();
  lcd.clear();
  lcd.print("welcome");
  delay(1000);
}
void loop()
{

  int x=digitalRead(ir);
```

```
int y=digitalRead(ir1);
int z=digitalRead(ir2);
int w=digitalRead(ir3);
//int u=digitalRead(ir4);
Serial.print("ir:;");
Serial.println(x);
delay(1000);
Serial.print("ir1:");
Serial.println(y);
delay(1000);
Serial.print("ir2:;");
Serial.println(z);
delay(1000);
Serial.print("ir3:");
Serial.println(w);
delay(1000);
if(x==0)
{
  Serial.println("slot::1 is full");
  lcd.clear();
  lcd.print("slot::1 is full");
  delay(1000);
}
else
{
    Serial.println("slot::1 is emt");
    lcd.clear();
    lcd.print("slot::1 is emt");
    delay(1000);
}
 if(y==0)
```

```
{
  Serial.println("slot::2 is full");
  lcd.clear();
  lcd.print("slot::2 is full");
  delay(1000);
}
else
{
   Serial.println("slot::2 is emt");
   lcd.clear();
   lcd.print("slot::2 is emt");
  delay(1000);
}
if(z==0)
{
  Serial.println("slot::3 is full");
  lcd.clear();
  lcd.print("slot::3 is full");
  delay(1000);
}
else
{
   Serial.println("slot::3 is emt");
   lcd.clear();
   lcd.print("slot::3 is emt");
  delay(1000);
}
 if(w==0)
{
  Serial.println("slot::4 is full");
  lcd.clear();
```

```
   lcd.print("slot::4 is full");
   delay(1000);
  }
  else
  {
    Serial.println("slot::4 is emt");
    lcd.clear();
    lcd.print("slot::4 is emt");
   delay(1000);
  }
  while (rfid.available())
  {
   rcv = rfid.readString();
   Serial.println(rcv);
 if(rcv=="5500199AB660")
 {
 int pos;
 Serial.println("rcv");
 for (pos = 0; pos <= 180; 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 15ms for the servo to reach the position
  }
  for (pos = 180; pos >= 0; pos -= 1) {  // goes from 180 degrees to 0 degrees
   myservo.write(pos);              // tell servo to go to position in variable 'pos'
   delay(15);                       // waits 15ms for the servo to reach the position
  }
 }
delay(50);
           }
}
```