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#include <AFMotor.h> //Ada fruit motor shield AF_DCMotor motor(1,MOTOR12_8KHZ); //Motor Initialization AF_DCMotor motor1(2,MOTOR12_8KHZ); const int Ps=A0; //Proximity sensor initialization int input = 0; // Variable declaration void setup() { motor.setSpeed(200); //Setting motor speed to 200 RPM motor1.setSpeed(200); //Setting second motor speed to 200 RPM Serial.begin(9600); } void loop() { if(digitalRead(Ps)==HIGH) //Check the sensor output { digitalWrite(13, HIGH); Serial.println("no obstacles"); // Set the LED off, no obstacle is present so the bot can move forward motor1.run(FORWARD); //Bot moves in forward direction motor.run(FORWARD); } else { digitalWrite(13, LOW); motor.run(RELEASE); //Making the bot stop motor1.run(RELEASE); Serial.println("obstacles Ahead"); // Set the LED to switch on } input = analogRead(Ps); Serial.println(input); delay(1000); }

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