#include<Servo.h>

Servo sg90;

#define sol\_motor\_ileri 10

#define sag\_motor\_ileri 4

#define sol\_motor\_geri 11

#define sag\_motor\_geri 2

#define fan 8

#define sol\_led 9

#define sag\_led 6

#define motor\_vcc 5

int sol\_cny = 0;

int sag\_cny = 0;

int alev\_sol = 0;

int alev\_sag = 0;

void setup()

{

// put your setup code here, to run once:

Serial.begin(9600); //iletişim ayarı

pinMode(sol\_motor\_ileri, OUTPUT);

pinMode(sol\_motor\_geri, OUTPUT);

pinMode(sag\_motor\_ileri, OUTPUT);

pinMode(sag\_motor\_geri, OUTPUT);

pinMode(fan, OUTPUT);

pinMode(sol\_led, OUTPUT);

pinMode(sag\_led, OUTPUT);

pinMode(motor\_vcc, OUTPUT);

digitalWrite(sol\_motor\_ileri, LOW);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, LOW);

digitalWrite(sag\_motor\_geri, LOW);

digitalWrite(sol\_led, LOW);

digitalWrite(sag\_led, LOW);

digitalWrite(motor\_vcc, HIGH);

for (int a = 0; a < 20 ; a++)

{

digitalWrite(sol\_led, HIGH);

digitalWrite(sag\_led, LOW);

delay(100);

digitalWrite(sol\_led, LOW);

digitalWrite(sag\_led, HIGH);

delay(100);

}

digitalWrite(sol\_led, LOW);

digitalWrite(sag\_led, LOW);

sg90.attach(3);

sg90.write(60);

digitalWrite(fan, HIGH);

delay(1000);

digitalWrite(fan, LOW);

}

void loop() {

// put your main code here, to run repeatedly:

sg90.attach(3);

sg90.write(60);

digitalWrite(fan, LOW);

digitalWrite(sol\_led, LOW);

digitalWrite(sag\_led, LOW);

const byte sol\_cizgi = A3;

sol\_cny = analogRead(sol\_cizgi );

const byte sag\_cizgi = A4;

sag\_cny = analogRead(sag\_cizgi );

Serial.print("sol = ");Serial.print(sol\_cny);Serial.print(" sag = ");Serial.println(sag\_cny);

const byte sol\_alev = A1;

alev\_sol = analogRead(sol\_alev );

const byte sag\_alev = A2;

alev\_sag = analogRead(sag\_alev );

// cny beyaz da 350 siyahta 800

// alev varken 35 alev yokken 100

while (alev\_sol < 200) // solda alev var

{

digitalWrite(sol\_motor\_ileri, LOW);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, LOW);

digitalWrite(sag\_motor\_geri, LOW);

digitalWrite(sol\_led, HIGH);

digitalWrite(sag\_led, LOW);

sg90.attach(3);

sg90.write(130);

delay (1000);

digitalWrite(fan, HIGH);

delay (2000);

digitalWrite(fan, LOW);

delay (2000);

const byte sol\_alev = A1;

alev\_sol = analogRead(sol\_alev );

}

while (alev\_sag < 200) // sagda alev var

{

digitalWrite(sol\_motor\_ileri, LOW);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, LOW);

digitalWrite(sag\_motor\_geri, LOW);

digitalWrite(sol\_led, LOW);

digitalWrite(sag\_led, HIGH);

sg90.attach(3);

sg90.write(0);

delay (1000);

digitalWrite(fan, HIGH);

delay (2000);

digitalWrite(fan, LOW);

delay (2000);

const byte sag\_alev = A2;

alev\_sag = analogRead(sag\_alev );

}

Serial.print ("sol cizgi = "); Serial.println (sol\_cny);

Serial.print ("sag cizgi = "); Serial.println (sag\_cny);

Serial.print ("sol alev = "); Serial.println (alev\_sol);

Serial.print ("sag alev = "); Serial.println (alev\_sag);

Serial.println ("\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*");

if (sol\_cny < 150 && sag\_cny < 150)

{

digitalWrite(sol\_motor\_ileri, HIGH);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, HIGH);

digitalWrite(sag\_motor\_geri, LOW);

delay(20);

digitalWrite(sol\_motor\_ileri, LOW);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, LOW);

digitalWrite(sag\_motor\_geri, LOW);

delay(10); //\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*parantez içindeki 5 i değiştireceksiniz hız ayarı için azaltırsanız hızlanır arttırırsanız yavaşlar

const byte sol\_cizgi = A3;

sol\_cny = analogRead(sol\_cizgi );

const byte sag\_cizgi = A4;

sag\_cny = analogRead(sag\_cizgi );

}

if (sol\_cny > 150 && sag\_cny < 150)

{

digitalWrite(sol\_motor\_ileri, LOW);

digitalWrite(sol\_motor\_geri, HIGH);

digitalWrite(sag\_motor\_ileri, HIGH);

digitalWrite(sag\_motor\_geri, LOW);

delay(300);

digitalWrite(sol\_motor\_ileri, LOW);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, LOW);

digitalWrite(sag\_motor\_geri, LOW);

delay(1);

const byte sol\_cizgi = A3;

sol\_cny = analogRead(sol\_cizgi );

const byte sag\_cizgi = A4;

sag\_cny = analogRead(sag\_cizgi );

}

if (sol\_cny < 150 && sag\_cny > 150)

{

digitalWrite(sol\_motor\_ileri, HIGH);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, LOW);

digitalWrite(sag\_motor\_geri, HIGH);

delay(300);

digitalWrite(sol\_motor\_ileri, LOW);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, LOW);

digitalWrite(sag\_motor\_geri, LOW);

delay(1);

const byte sol\_cizgi = A3;

sol\_cny = analogRead(sol\_cizgi );

const byte sag\_cizgi = A4;

sag\_cny = analogRead(sag\_cizgi );

}

if (sol\_cny > 150 && sag\_cny > 150)

{

digitalWrite(sol\_motor\_ileri, LOW);

digitalWrite(sol\_motor\_geri, LOW);

digitalWrite(sag\_motor\_ileri, LOW);

digitalWrite(sag\_motor\_geri, LOW);

digitalWrite(sol\_led, HIGH);

digitalWrite(sag\_led, HIGH);

delay (100);

digitalWrite(sol\_led, LOW);

digitalWrite(sag\_led, LOW);

delay (100);

const byte sol\_cizgi = A3;

sol\_cny = analogRead(sol\_cizgi );

const byte sag\_cizgi = A4;

sag\_cny = analogRead(sag\_cizgi );

}

}