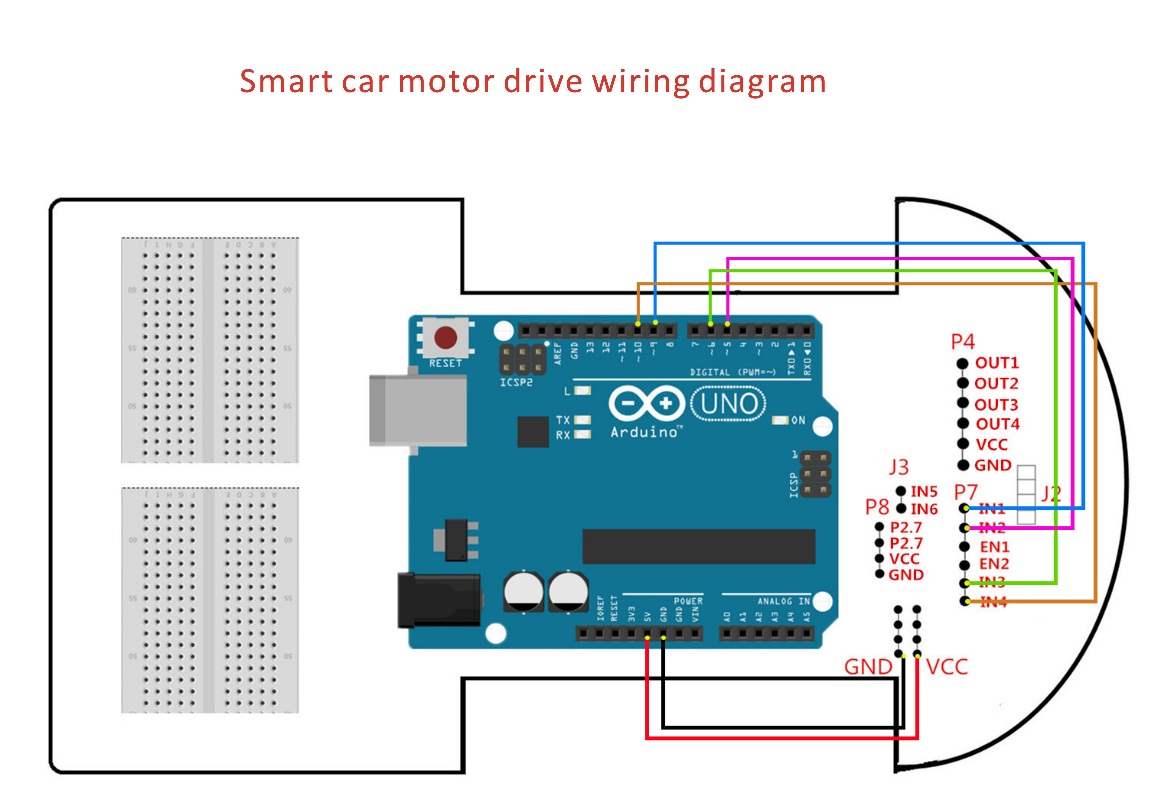
**Movimientos especiales**

1. Funcionamiento



1. Código

int Left\_motor\_back=9; //(IN1)

int Left\_motor\_go=5; //(IN2)

int Right\_motor\_go=6; //(IN3)

int Right\_motor\_back=10; //(IN4)

void setup()

{

pinMode(Left\_motor\_go,OUTPUT);

pinMode(Left\_motor\_back,OUTPUT);

pinMode(Right\_motor\_go,OUTPUT);

pinMode(Right\_motor\_back,OUTPUT);

}

void run(int time)

{

digitalWrite(Right\_motor\_go,HIGH);

digitalWrite(Right\_motor\_back,LOW);

analogWrite(Right\_motor\_go,200);

analogWrite(Right\_motor\_back,0);

digitalWrite(Left\_motor\_go,HIGH);

digitalWrite(Left\_motor\_back,LOW);

analogWrite(Left\_motor\_go,200);

analogWrite(Left\_motor\_back,0);

delay(time \* 100);

}

void brake(int time)

{

digitalWrite(Right\_motor\_go,LOW);

digitalWrite(Right\_motor\_back,LOW);

digitalWrite(Left\_motor\_go,LOW);

digitalWrite(Left\_motor\_back,LOW);

delay(time \* 100);

}

void left(int time)

{

digitalWrite(Right\_motor\_go,HIGH);

digitalWrite(Right\_motor\_back,LOW);

analogWrite(Right\_motor\_go,200);

analogWrite(Right\_motor\_back,0);

digitalWrite(Left\_motor\_go,LOW);

digitalWrite(Left\_motor\_back,LOW);

analogWrite(Left\_motor\_go,0);

analogWrite(Left\_motor\_back,0);

delay(time \* 100);

}

void spin\_left(int time)

{

digitalWrite(Right\_motor\_go,HIGH);

digitalWrite(Right\_motor\_back,LOW);

analogWrite(Right\_motor\_go,200);

analogWrite(Right\_motor\_back,0);

digitalWrite(Left\_motor\_go,LOW);

digitalWrite(Left\_motor\_back,HIGH);

analogWrite(Left\_motor\_go,0);

analogWrite(Left\_motor\_back,200);

delay(time \* 100);

}

void right(int time)

{

digitalWrite(Right\_motor\_go,LOW);

digitalWrite(Right\_motor\_back,LOW);

analogWrite(Right\_motor\_go,0);

analogWrite(Right\_motor\_back,0);

digitalWrite(Left\_motor\_go,HIGH);

digitalWrite(Left\_motor\_back,LOW);

analogWrite(Left\_motor\_go,200);

analogWrite(Left\_motor\_back,0);

delay(time \* 100);

}

void spin\_right(int time)

{

digitalWrite(Right\_motor\_go,LOW);

digitalWrite(Right\_motor\_back,HIGH);

analogWrite(Right\_motor\_go,0);

analogWrite(Right\_motor\_back,200);

digitalWrite(Left\_motor\_go,HIGH);

digitalWrite(Left\_motor\_back,LOW);

analogWrite(Left\_motor\_go,200);

analogWrite(Left\_motor\_back,0);

delay(time \* 100);

}

void back(int time)

{

digitalWrite(Right\_motor\_go,LOW);

digitalWrite(Right\_motor\_back,HIGH);

analogWrite(Right\_motor\_go,0);

analogWrite(Right\_motor\_back,150);

digitalWrite(Left\_motor\_go,LOW);

digitalWrite(Left\_motor\_back,HIGH);

analogWrite(Left\_motor\_go,0);

analogWrite(Left\_motor\_back,150);

delay(time \* 100);

}

void loop()

{

int i;

delay(2000);

run(10);

back(10);

brake(5);

for(i=0;i<5;i++)

{

run(10);

brake(1);

}

for(i=0;i<5;i++)

{

back(10);

brake(1);

}

for(i=0;i<5;i++)

{

left(10);

spin\_left(5);

}

for(i=0;i<5;i++)

{

right(10);

spin\_right(5);

}

for(i=0;i<10;i++)

{

right(1);

brake(1);

}

for(i=0;i<10;i++)

{

left(1);

brake(1);

}

for(i=0;i<10;i++)

{

left(3);

right(3);

}

for(i=0;i<10;i++)

{

spin\_left(3);

brake(3);

}

for(i=0;i<10;i++)

{

spin\_right(3);

brake(3);

}

}