// pin tanımlamaları//

#define trigpin 13

#define echopin 2

#define ENBA 5

#define in1 3

#define in2 4

#define in3 9

#define in4 11

#define ENBB 12

//değişken tanımlaması//

int son,durum,i;

void setup() {

Serial.begin(9600);

////sensör pinlerinin ayarlanması//////

pinMode(trigpin, OUTPUT);

pinMode(echopin, INPUT);

pinMode(in1, OUTPUT);

pinMode(in2, OUTPUT);

pinMode(in3, OUTPUT);

pinMode(in4, OUTPUT);

pinMode(ENBA, OUTPUT);

pinMode(ENBB, OUTPUT);

digitalWrite(ENBA, HIGH);

digitalWrite(ENBB, HIGH);

}

/////sensör1 algılama fonksiyonu///

float sonarSensor ()

{

digitalWrite(trigpin, HIGH);

delayMicroseconds (2);

digitalWrite(trigpin,LOW);

delayMicroseconds(10);

son = pulseIn (echopin, HIGH);

son = son/58.1;

return(son);

}

/////robot dur/////

void robotdur()

{

/\*digitalWrite(in1, LOW);

digitalWrite(in2, LOW);

digitalWrite(in3, LOW);

digitalWrite(in4, LOW);

\*/

digitalWrite(ENBA, LOW);

digitalWrite(ENBB, LOW);

delay(500);

digitalWrite(ENBA, HIGH);

digitalWrite(ENBB, HIGH);

}

//////robot ileri fonksiyonu/////

void robotileri()

{

digitalWrite(in2, LOW);

analogWrite(in1, 100);

//digitalWrite(in1, HIGH);

digitalWrite(in4, LOW);

analogWrite(in3, 100);

// digitalWrite(in3, HIGH);

}

/////robot ileri sağ////

void robotsagileri()

{

digitalWrite(in1, LOW);

digitalWrite(in2, LOW);

digitalWrite(in4, LOW);

analogWrite(in3, 100);

//digitalWrite(in3, HIGH);

}

/////robot sol ileri///////

void robotsolileri()

{

digitalWrite(in1, HIGH);

digitalWrite(in2, LOW);

digitalWrite(in3, LOW);

digitalWrite(in4, LOW);

}

void loop()

{

durum = sonarSensor ();

Serial.println(durum);

if(durum > 0 && durum< 20)

{

robotdur();

durum = sonarSensor ();

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

// {

robotsagileri();

//durum = sonarSensor ();

delay(1000);

// i++;

// }

}

robotileri();

}