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#include<AFMotor.h>

AF_DCMotor motor1(1, MOTOR12_1KHZ);
AF_DCMotor motor2(2,
MOTOR12_1KHZ);
AF_DCMotor motor3(3, MOTOR12_1KHZ);
AF_DCMotor motor4(4, MOTOR12_1KHZ);

int
tx = 1;
int rx = 0;

char inSerial[15];
char command;

void setup()
{

Serial.begin(9600); //Set the baud rate to your Bluetooth module.
}

void loop() {

    int
i = 0;
    int m = 0
    ;
    delay(500);
    if (Serial.available() > 0) {
        while
(Serial.available() > 0) {
            inSerial[i] = Serial.read();
            i++;
        }

inSerial[i] = '\0';
        Check_Protocol(inSerial);
    }
}

void Check_Protocol(char inStr[])
{
    int i = 0;
    int m = 0;
    Serial.println(inStr);

    if (!strcmp(inStr,
"*forward#")) {
        forward();
        delay(1200);

        for (m = 0; m < 11;
m++) {
            inStr[m] = 0;
        }
        i = 0;
    }

    if (!strcmp(inStr,
"*back#")) {
        back();
        delay(500);

        for (m = 0; m < 11; m++) {

            inStr[m] = 0;
        }
        i = 0;
    }

    if (!strcmp(inStr, "*left#")) {

left();
        delay(150);

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    for (m = 0; m < 11; m++) {
        inStr[m] = 0;
    }

    i = 0;
}
if (!strcmp(inStr, "*right#")) {
    right();
    delay(150);

    for (m = 0; m < 11; m++) {
        inStr[m] = 0;
    }
    i = 0;
}

if
(!strcmp(inStr, "*stop#")) {
    Stop();
    for (m = 0; m < 11; m++) {

inStr[m] = 0;
    }
    i = 0;
}

else {
    for (m = 0; m < 11; m++) {

inStr[m] = 0;
    }
    i = 0;
}
}

void forward()
{
    motor1.setSpeed(255);

motor1.run(FORWARD);
    motor2.setSpeed(255);
    motor2.run(FORWARD);

motor3.setSpeed(255);
    motor3.run(FORWARD);
    motor4.setSpeed(255);

motor4.run(FORWARD);
}

void back()
{
    motor1.setSpeed(255);
    motor1.run(BACKWARD);

motor2.setSpeed(255);
    motor2.run(BACKWARD);
    motor3.setSpeed(255);

motor3.run(BACKWARD);
    motor4.setSpeed(255);
    motor4.run(BACKWARD);
}

void left()
{
    motor1.setSpeed(255);
    motor1.run(FORWARD);
    motor2.setSpeed(255);

motor2.run(FORWARD);

```

```
    motor3.setSpeed(0);
    motor3.run(RELEASE);
    motor4.setSpeed(0);

motor4.run(RELEASE);
}

void right()
{
    motor1.setSpeed(0);
    motor1.run(RELEASE);

motor2.setSpeed(0);
    motor2.run(RELEASE);
    motor3.setSpeed(255);
    motor3.run(FORWARD);

motor4.setSpeed(255);
    motor4.run(FORWARD);
}

void Stop()
{
    motor1.setSpeed(0);

motor1.run(RELEASE);
    motor2.setSpeed(0);
    motor2.run(RELEASE);
    motor3.setSpeed(0);

motor3.run(RELEASE);
    motor4.setSpeed(0);
    motor4.run(RELEASE);
}
```