```
`#include <SoftwareSerial.h>

Servo myservo;
const int mot11=2 ;
const int mot12=3;
const int mot21=4;//rotation motor connections
const int mot22=5;
const int mot31=6;
const int mot32=7;
const int mot41=11;
const int mot42=12;
const int relay =10;
SoftwareSerial portOne(8,9);
int pos = 0;
char byt;

void setup()
{
  pinMode(mot11,OUTPUT);
   pinMode(mot12,OUTPUT);
    pinMode(mot21,OUTPUT);
     pinMode(mot22,OUTPUT);
     pinMode(mot31,OUTPUT);
     pinMode(mot32,OUTPUT);
     pinMode(mot41,OUTPUT);
     pinMode(mot42,OUTPUT);
       pinMode(relay,OUTPUT);
       digitalWrite(relay,HIGH);
```

```
     Serial.begin(9600);
    portOne.begin(9600);

     }

void loop()
{
  while(1)
  {
if(portOne.available()>0)
{
char byt= portOne.read();
Serial.write(byt);
    switch(byt)
   {
   case '1':
   {
     digitalWrite(mot11,HIGH);
  digitalWrite(mot12, LOW);
 digitalWrite(mot21, HIGH);
  digitalWrite(mot22, LOW);
   Serial.println("forward");
  delay(2000);
   break;
   }
  case '2':
   {
    digitalWrite(mot11,LOW);
  digitalWrite(mot12, HIGH);
```

```
 digitalWrite(mot21, LOW);
  digitalWrite(mot22, HIGH);
    Serial.println("reverse");
   delay(2000);
   break;
     }
     case '3':
   {
digitalWrite(mot11,LOW);
  digitalWrite(mot12, HIGH);
 digitalWrite(mot21, HIGH);
  digitalWrite(mot22, LOW);
  Serial.println("LEFT");
  delay(2000);
  break;
   }
   case '4':
   {

 digitalWrite(mot11,HIGH);
  digitalWrite(mot12, LOW);
 digitalWrite(mot21, LOW);
  digitalWrite(mot22, HIGH);
    Serial.println("RIGHT");
    delay(2000);
 break;
   }
case '5':
   {
```

```
  digitalWrite(mot11,LOW);
 digitalWrite(mot12, LOW);
digitalWrite(mot21, LOW);
 digitalWrite(mot22, LOW);
     Serial.println("STOP");
     delay(2000);

   break;
  }
  case '6':
  {
 digitalWrite(relay,LOW);
 Serial.println("PUMP ON");
       break;
  }
    case '7':
  {
 digitalWrite(relay,HIGH);
 Serial.println("PUMP OFF");
       break;
  }
     case '8':
  {
 digitalWrite(mot31,HIGH);
digitalWrite(mot32,LOW);
 Serial.println("TOP ON");
       break;
  }
     case '9':
```

```
  {
  digitalWrite(mot31,LOW);
digitalWrite(mot32,HIGH);
  Serial.println("TOP OFF");
        break;
  }
   case '0':
  {
  digitalWrite(mot31,LOW);
digitalWrite(mot32,LOW);
  Serial.println("TOP OFF");
        break;
  }
     case 'a':
  {
     digitalWrite(mot41,LOW);
digitalWrite(mot42,HIGH);
delay(1000);
 digitalWrite(mot41,HIGH);
digitalWrite(mot42,LOW);
delay(1000);
 digitalWrite(mot41,LOW);
digitalWrite(mot42,LOW);
delay(1000);
  break;
  }

      default:
    {
```

```
      break;


    }
   }

}


}
}
/*void checkfire()  {
  st=digitalRead(SensorPin);
  if(st==LOW)
  {
portOne.println("fire occured");
Serial.println("fire occured");
  digitalWrite(mot11,LOW);
  digitalWrite(mot12, LOW);
 digitalWrite(mot21, LOW);
  digitalWrite(mot22, LOW);
   digitalWrite(pump,LOW);
   delay(2000);
     digitalWrite(pump,HIGH);
   delay(2000);
  }
}*/
```