Task (7): Line follower car

```
#define speedL 10
#define IN1 9
#define IN2 8
#define IN3 7
#define IN4 6
#define speedR 5
#define sensorL 4
#define sensorR 3
int sl=0;
int sr=0;
void setup() {
for (int i=5; i<=10; i++)
{
pinMode (i, OUTPUT);
}
pinMode (sensorR, INPUT);
pinMode (sensorL, INPUT);
}
void forward()
{
digitalWrite (IN1, HIGH);
digitalWrite (IN2, LOW);
digitalWrite (IN3, HIGH);
digitalWrite (IN4, LOW);
analogWrite (speedL, 150);
analogWrite (speedR, 150);
}
void backward()
{
digitalWrite (IN1, LOW);
digitalWrite (IN2, HIGH);
digitalWrite (IN3, LOW);
digitalWrite (IN4, HIGH);
analogWrite (speedL, 150);
analogWrite (speedR, 150);
}
void left()
{
digitalWrite (IN1, LOW);
digitalWrite (IN2, LOW);
digitalWrite (IN3, HIGH);
digitalWrite (IN4, LOW);
analogWrite (speedL, 0);
analogWrite (speedR, 120);
}
```

```
void right()
{
digitalWrite (IN1, HIGH);
digitalWrite (IN2, LOW);
digitalWrite (IN3, LOW);
digitalWrite (IN4, LOW);
analogWrite (speedL, 120);
analogWrite (speedR, 0);
}
void stopp()
{
digitalWrite (IN1, LOW);
digitalWrite (IN2, LOW);
digitalWrite (IN3, LOW);
digitalWrite (IN4, LOW);
analogWrite (speedL, 0);
analogWrite (speedR, 0);
}

void loop() {
sl=digitalRead (sensorL);
sr=digitalRead (sensorR);
if (sl==0&&sr==0) {
forward();}
else if (sl==0&&sr==1){
right();}
else if (sl==1&&sr==0){
left();}
else if (sl==1&&sr==1){
stopp();}
}
```