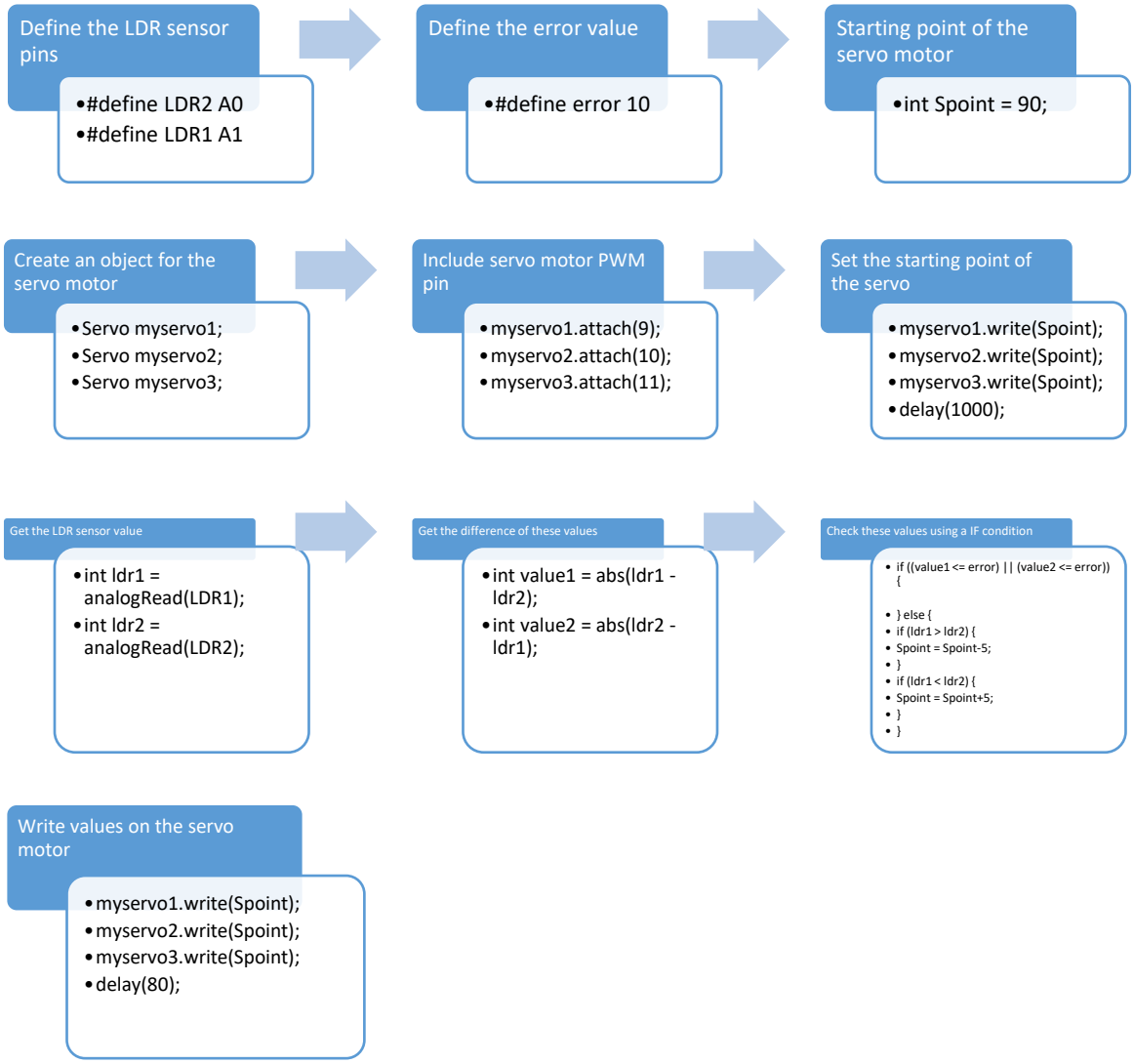
Define the LDR sensor pins
•#define LDR2 A0
•#define LDR1 A1
Define the error value
•#define error 10
Starting point of the servo motor
•int Spoint = 90;
Create an object for the servo motor
•Servo myservo1;
•Servo myservo2;
•Servo myservo3;
Include servo motor PWM pin
•myservo1.attach(9);
•myservo2.attach(10);
•myservo3.attach(11);
Set the starting point of the servo
•myservo1.write(Spoint);
•myservo2.write(Spoint);
•myservo3.write(Spoint);
•delay(1000);
Get the LDR sensor value
•int ldr1 = analogRead(LDR1);
•int ldr2 = analogRead(LDR2);
Get the difference of these values
•int value1 = abs(ldr1 - ldr2);
•int value2 = abs(ldr2 - ldr1);
Check these values using a IF condition
• if ((value1 <= error) || (value2 <= error)) {
• } else {
• if (ldr1 > ldr2) {
• Spoint = Spoint-5;
• }
• if (ldr1 < ldr2) {
• Spoint = Spoint+5;
• }
• }
Write values on the servo motor
•myservo1.write(Spoint);
•myservo2.write(Spoint);
•myservo3.write(Spoint);
•delay(80);