#include <LiquidCrystal.h>

LiquidCrystal lcd(8,9,10,11,12,13);

#include <Servo.h>

Servo myservo;

#define alm 2

int ult,u2,ss=0,xAccl;

int Temp,Level,pol,dir,spd,dirr,xaxis,yaxis,zaxis,gas,temp,bat,mic,hum,sett,x,y;

int speed1,spe,speed2;

int pos = 0,pos1 = 0,mappedValue1;

unsigned char EB,unit,amt,at=0;

unsigned char xx = 0;

unsigned char irv,irvv,irvvv,sec6,yu=0,val[20];

String irv2;

int countTrueCommand,sec=0,secc=0;

int countTimeCommand;

boolean found = false;

int valSensor = 100;

 int motor\_speed;

int motor\_speed1;

float units;

float ounces;

void setup()

{

  pinMode(alm,OUTPUT);digitalWrite(alm,LOW);

  Serial.begin(9600);

  myservo.attach(A0);

  lcd.begin(16, 2);

  lcd.setCursor(0,0);

  lcd.print("----------------");

  lcd.setCursor(0,1);

  lcd.print("----------------"); delay(2000);

      lcd.clear();

  }

void loop()

{

x=analogRead(A1)>>2;

  mappedValue1 = map(x, 0, 255, 100, 0);

  if(mappedValue1<45){mappedValue1=0;}

  lcd.setCursor(0,0);

  lcd.print("RAIN:");

  Lcd\_Decimal3(5,0,mappedValue1); lcd.print("%");

  delay(10);

   if(mappedValue1>=65)

    {  ss=3;

   lcd.setCursor(0, 1);

   lcd.print("    RAIN HIGH   ");// digitalWrite(alm,HIGH); http\_send1();delay(1000);digitalWrite(alm,LOW);

  for (pos = 90; pos >= 0; pos -= 1) { // goes from 180 degrees to 0 degrees

  myservo.write(pos);              // tell servo to go to position in variable 'pos'

  delay(10);                        // waits 15ms for the servo to reach the position

  }

  for (pos = 0; pos <= 90; pos += 1) { // goes from 180 degrees to 0 degrees

    myservo.write(pos);              // tell servo to go to position in variable 'pos'

    delay(10);

   }

  }

  else if(mappedValue1>=10)

    {  ss=3;

   lcd.setCursor(0, 1);

   lcd.print("   RAIN SLOW    ");// digitalWrite(alm,HIGH); http\_send1();delay(1000);digitalWrite(alm,LOW);

  for (pos = 90; pos >= 0; pos -= 1) { // goes from 180 degrees to 0 degrees

  myservo.write(pos);              // tell servo to go to position in variable 'pos'

  delay(50);                        // waits 15ms for the servo to reach the position

  }

  for (pos = 0; pos <= 90; pos += 1) { // goes from 180 degrees to 0 degrees

    myservo.write(pos);              // tell servo to go to position in variable 'pos'

    delay(50);

   }

  }

  else{

     lcd.setCursor(0, 1);

   lcd.print("     NORMAL     ");

    myservo.write(90);              // tell servo to go to position in variable 'pos'

    delay(15);

   }

    }