```
//#include <ArduinoRobot.h>
//#include <Wire.h>
#include<Servo.h>



Servo servoRight;
Servo servoLeft;
unsigned long startTime=0;



void setup() {
  //Serial.begin(9600);


  servoLeft.attach(13);
  servoRight.attach(12);
  pinMode(11, OUTPUT);
  pinMode(6, OUTPUT);
}


void loop() {

serial .print(“Goodnight moon”);
delay(200)
serial.printin(“ “);




  unsigned long loopTime= millis() - startTime;
  if (loopTime<= 5000){
  servoLeft.write(0);
  servoRight.write(180);
  delay(300); //forward

  servoLeft.write(0);
  servoRight.write(0);
  delay(300); //turn left

  servoLeft.write(0);
```

```
  servoRight.write(180);
  delay(300); //forward

  servoLeft.write(0);
  servoRight.write(0);
  delay(300); //turn left
//
//  for (int pos=0;pos<=180;pos+=1){
//  servoLeft.write(pos);
//  servoRight.write(pos);
//  }
  }
  else {
  servoLeft.write(0);
  servoRight.write(0);
  delay(300); //turn left

  servoLeft.write(180);
  servoRight.write(180);
  delay(300); //turn right

  }

 for (int pos=180;pos>=0;pos-=1){
  servoLeft.write(pos);
  //delay.microseconds(1000);
  servoRight.write(pos);

  servoLeft.writeMicroseconds(1300);   // Left wheel clockwise
  servoRight.writeMicroseconds(1300);  // Right wheel clockwise
//
//  servoLeft.writeMicroseconds(1700);         // Left wheel counterclockwise
//  servoRight.writeMicroseconds(1700);        // Right wheel counterclockwise
//  delay(600);                                // ...for 0.6 seconds

 // Turn right in place
 servoLeft.writeMicroseconds(1700);   // Left wheel counterclockwise servoRight.write
Microseconds(1700); // Right wheel counterclockwise
 }
  digitalWrite(6,HIGH);
  delay(10);
  digitalWrite(6,LOW);
  delay (10);
```

```
  digitalWrite(11, HIGH);
  delay(5);
  digitalWrite(11, LOW);
  delay(5);



}

//55sec Valentino Khan Deep Down Low
```