1. Ultrasonic.h à UTSN
   1. Constructor: Ultrasonic(int trigPin);
   2. Method:

* Float measDist(int echoPin);
  + Return Dist;

1. Motor\_Driver.h à driver
   1. Constructor: Motor\_Driver(int IN1, int IN2, int IN3, int IN4);
   2. Methods:

* Void stopCar();
* Void forward();
* Void backward();
* Void turnRight();
* Void turnLeft();

1. Encoder\_Read.h à encoder
   1. Constructor: Encoder\_Read();
   2. Methods:

* Bool noIntrFound(unsigned long dfr\_time, int wait\_time);
  + Return true;
* Float velo\_cal(int RPM);
  + Return v;
* Float dist\_cal(int count);
  + Return dist;
* Float angle\_cal(int leftCount, int rightCount);
  + Return angle;

1. LFsensor.h à LFS
   1. Constructor: LFsensor(int S1, int S2, int S3, int S4, int S5);
   2. Methods:

* Void readLFsensor(int mode, float error);
* Void testLineFollowSensor();
* Float errorVal();
  + Return error;
* Float modeVal();
  + Return mode;