char t;

void setup() {

pinMode(13,OUTPUT); //leftA motors forward

pinMode(12,OUTPUT); //leftA motors reverse

pinMode(11, OUTPUT); //rightB motor forward

pinMode(10, OUTPUT); //rightB motr reverse

pinMode(6, OUTPUT); //ENB

pinMode(5, OUTPUT); //ENA

Serial.begin(9600);

}

void loop() {

if(Serial.available()){

t = Serial.read();

Serial.println(t);

}

if(t == 'F'){ //move forward(all motors rotate in forward direction)

digitalWrite(13,HIGH);

digitalWrite(12,LOW);

digitalWrite(11,HIGH);

digitalWrite(10,LOW);

analogWrite(5, 255);

analogWrite(6, 255);

}

else if(t == 'B'){ //move reverse (all motors rotate in reverse direction)

digitalWrite(13,LOW);

digitalWrite(12,HIGH);

digitalWrite(11,LOW);

digitalWrite(10,HIGH);

analogWrite(5, 255);

analogWrite(6, 255);

}

else if(t == 'L'){ //turn LEFT (left side motors rotate in forward direction, right side motors doesn't rotate)

digitalWrite(13,HIGH);

digitalWrite(12,LOW);

digitalWrite(11,HIGH);

digitalWrite(10,LOW);

analogWrite(5, 255);

analogWrite(6, 0);

}

else if(t == 'R'){ //turn RIGHT (right side motors rotate in forward direction, left side motors doesn't rotate)

digitalWrite(13,HIGH);

digitalWrite(12,LOW);

digitalWrite(11,HIGH);

digitalWrite(10,LOW);

analogWrite(5, 0);

analogWrite(6, 255);

}

else if(t == 'S'){ //STOP (all motors stop)

digitalWrite(13,LOW);

digitalWrite(11,LOW);

digitalWrite(12,LOW);

digitalWrite(10,LOW);

}

delay(100);

}