```
#include <stdio.h>

#include <stdio.h>

#include<string.h>

int ldr 1 = A0; int ldr

2 = A1; int ldr 3 =

A2; int ldr 4 = A3;

int ldr val 1, ldr val 2, ldr val 3, ldr val 4; int

motor 1= 4; int motor 2= 5; int motor 3= 6;

int motor 4= 7; char ch; void setup()

{

        serial.begin(9600);        pin

mode(ldr 1,input);        pin

mode(ldr 2,input);        pin

mode(ldr 3,input);        pin

mode(ldr 4,input);        digital

write(motor 1,low);        digital

write(motor 2,low);        digital

write(motor 3,low);        digital

write(motor 4,low);

}

void loop()

{

        auto_mode();

} void

auto_mode()

{
```

```
        while(1)
} ldr val1= analog
read(ldr1); ldr
val1=1023_ldr val1;

//serial.print("ldr value");
//serial.print("ldr value1");
delay(100); ldr val2=
analog read(ldr2); ldr
val2=1023_ldr val2;

//serial.print("ldr value");
//serial.print("ldr value2");
delay(100); ldr val3=
analog read(ldr3); ldr
val3=1023_ldr val3;

//serial.print("ldr value");
//serial.print("ldr value3");
delay(100); ldr val4=
analog read(ldr4); ldr
val4=1023_ldr val3;

//serial.print("ldr value");
//serial.print("ldr value4");
delay(100);
if(ldr val 1>700)
{
```

```
        serial.print("A");      digital

write(motor 1,high);        digital

write(motor 2,low);

        delay(100);

        digital write(motor 1,low);

        digital write(motor 1,low);

        delay(100);

} else if(ldr val

2>700)

{

        serial.print("B")      digital

write(motor 3,low);         digital

write(motor 4,high);

        delay(100);

        digital write(motor 3,low);

        digital write(motor 4,low);

        delay(100);

} else if(ldr val

3>700)

{

        serial.print("C");      digital

write(motor 1,low);         digital

write(motor 2,high);

        delay(100);
```

```
        digital write(motor 1,low);

        digital write(motor 2,low);

                delay(100);

else if(ldr val 4>700)

{

        serial.print("D");      digital

write(motor 3,high);          digital

write(motor 4,low);

        delay(100);

        digital write(motor 3,low);

        digital write(motor 4,low);

        delay(100);

}

}
```