```
#include <Wire.h>
#include<ArduinoJson.h>
#include <ESP8266WiFi.h>
#include <WiFiClientSecure.h>
#include <UniversalTelegramBot.h>


const char* ssid = "Naji";
const char* password = "987654321";


#define BOTtoken "6274286363:AAHaTXt0r_ftm01FC5uAAi_CiYucxUGdne0"
#define CHAT_ID "1008149071"
X509List cert(TELEGRAM_CERTIFICATE_ROOT);
WiFiClientSecure client;
UniversalTelegramBot bot(BOTtoken, client);
unsigned long bot_lasttime;
const unsigned long BOT_MTBS = 1000;
const int TRIGGER_PIN_1 = 13;
const int ECHO_PIN_1 = 15;
const int TRIGGER_PIN_2 = 14;
const int ECHO_PIN_2 = 12  ;
void motor();
void ultrasonic();
long duration1, distance1, duration2, distance2;
String  chat_id="";
String text="";
String from_name="";
int flag;

void setup() {
  Serial.begin(9600);
  configTime(0, 0, "pool.ntp.org");      // get UTC time via NTP
  client.setTrustAnchors(&cert); // Add root certificate for api.telegram.org
 WiFi.mode(WIFI_STA);
  WiFi.begin(ssid, password);

  int a = 0;
 while (WiFi.status() != WL_CONNECTED)
 {
    Serial.print(".");

    delay(500);
    a++;
  }
  Serial.println("WiFi connected");
  Serial.print("IP address: ");
   Serial.println(WiFi.localIP());
  delay(500);
  int numNewMessages = bot.getUpdates(bot.last_message_received + 1);
```

```
   Serial.println(numNewMessages);
  delay(1000);
   Serial.print("Retrieving time: ");
  time_t now = time(nullptr);
  while (now < 24 * 3600)
  {
    Serial.print(".");
    delay(100);
    now = time(nullptr);
  }
  Serial.println(now);


  pinMode(TRIGGER_PIN_1, OUTPUT);
  pinMode(ECHO_PIN_1, INPUT);
  pinMode(TRIGGER_PIN_2, OUTPUT);
  pinMode(ECHO_PIN_2, INPUT);
  pinMode(0,OUTPUT);
  pinMode(2,OUTPUT);
  pinMode(5,OUTPUT);
  pinMode(4,OUTPUT);
  pinMode(1,OUTPUT);
  pinMode(3,OUTPUT);
  pinMode(16,OUTPUT);


}

void loop() {

    if (millis() - bot_lasttime > BOT_MTBS)
  {
    int numNewMessages = bot.getUpdates(bot.last_message_received + 1);

    while (numNewMessages)
    {
      Serial.println("got response");
      handleNewMessages(numNewMessages);
      numNewMessages = bot.getUpdates(bot.last_message_received + 1);
    }

    bot_lasttime = millis();
  }

}
  void handleNewMessages(int numNewMessages)
{
  Serial.print("handleNewMessages ");
  Serial.println(numNewMessages);
```

```
  for (int i = 0; i < numNewMessages; i++)
  {
    String  chat_id = bot.messages[i].chat_id;
    String text= bot.messages[i].text;

    String from_name = bot.messages[i].from_name;
    if (from_name == "")
      from_name = "Najiya";

    if (text == "/start"){
      flag=1;



  }
  while(flag==1){
    motor();
  }
}
}

void motor(){


 digitalWrite(1,LOW);
 digitalWrite(3,LOW);
      digitalWrite(0,HIGH);
        digitalWrite(2,LOW);
          digitalWrite(5,HIGH);
            digitalWrite(4,LOW);

delay(2000);

 digitalWrite(1,HIGH);
 digitalWrite(3,LOW);
digitalWrite(0,LOW);
        digitalWrite(2,LOW);
          digitalWrite(5,LOW);
            digitalWrite(4,LOW);

            delay(3000);

            digitalWrite(1,LOW);
            digitalWrite(3,LOW);
            digitalWrite(0,LOW);
            digitalWrite(2,HIGH);
            digitalWrite(5,HIGH);
            digitalWrite(4,LOW);
            delay(2000);
            digitalWrite(1,HIGH);
```

```
 digitalWrite(3,LOW);
digitalWrite(0,LOW);
        digitalWrite(2,LOW);
          digitalWrite(5,LOW);
            digitalWrite(4,LOW);
            delay(3000);

            digitalWrite(1,LOW);
 digitalWrite(3,LOW);
      digitalWrite(0,HIGH);
        digitalWrite(2,LOW);
          digitalWrite(5,LOW);
            digitalWrite(4,HIGH);

            delay(2000);
             digitalWrite(1,HIGH);
 digitalWrite(3,LOW);
digitalWrite(0,LOW);
        digitalWrite(2,LOW);
          digitalWrite(5,LOW);
            digitalWrite(4,LOW);
            delay(3000);
            digitalWrite(1,LOW);
 digitalWrite(3,LOW);
      digitalWrite(0,LOW);
        digitalWrite(2,HIGH);
          digitalWrite(5,LOW);
            digitalWrite(4,HIGH);
            delay(2000);
            digitalWrite(1,HIGH);
 digitalWrite(3,LOW);
digitalWrite(0,LOW);
        digitalWrite(2,LOW);
          digitalWrite(5,LOW);
            digitalWrite(4,LOW);
            delay(3000);
}
```