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master code: #include<Wire.h> #include <SoftwareSerial.h> char data; SoftwareSerial softserial(0, 1); void setup() { softserial.begin(9600); Wire.begin(); pinMode(9,OUTPUT); digitalWrite(9,HIGH); Serial.begin(9600); } void loop() { if(softserial.available()) { data = softserial.read(); Serial.print(data); Wire.beginTransmission(9); // transmit to device #9 Wire.write(data); // sends the data Wire.endTransmission(); // stop transmitting } delay(500); } slave code: #include <AFMotor.h> #include<Wire.h> AF_DCMotor motor1(1, MOTOR12_1KHZ); AF_DCMotor motor2(2, MOTOR12_1KHZ); AF_DCMotor motor3(3, MOTOR34_1KHZ); AF_DCMotor motor4(4, MOTOR34_1KHZ); char data; void setup() { Wire.begin(9); Serial.begin(9600); Wire.onReceive(receiveEvent); } void receiveEvent(int bytes) { data=Wire.read(); Serial.println(data); } void loop() { switch (data) { case '1': //FORWARD- all 4 wheels in forward direction forward(); delay(2000); break; case '2': // REVERSE - all 4 wheels in backward direction backward(); delay(2000); break; case '3': // FORWARD LEFT left(); //motor 1 and 2 in backward direction motor 3 and 4 in foreward direction delay(1500); forward(); delay(2000); break; case '4': //FORWARD RIGHT right(); //motor 1 and 2 in forward direction motor 3 and 4 in backward direction delay(1500); forward(); delay(2000); break; case '5': //REVERSE LEFT right(); delay(1500); backward(); delay(2000); break; case '6': //REVERSE RIGHT left(); delay(1500); backward(); delay(2000); break; default: //If bluetooth module receives any value not listed above, then all the four motors stop running motor1.run(RELEASE); motor2.run(RELEASE); motor3.run(RELEASE); motor4.run(RELEASE); } } void forward() { motor1.setSpeed(127); //set motor1 to half speed max speed=255, min speed=0,half speed=127 motor1.run(FORWARD); //rotate the motor clockwise motor2.setSpeed(127); //set motor2 to half speed motor2.run(FORWARD); //rotate the motor clockwise motor3.setSpeed(127); //set motor3 to half speed motor3.run(FORWARD); //rotate the motor clockwise motor4.setSpeed(127); //set motor4 to half speed motor4.run(FORWARD); //rotate the motor clockwise } void backward() { motor1.setSpeed(127); //set motor1 to half speed max speed=255, min speed=0,half speed=127 motor1.run(BACKWARD); //rotate the motor clockwise motor2.setSpeed(127); //set motor2 to half speed motor2.run(BACKWARD); //rotate the motor clockwise motor3.setSpeed(127); //set motor3 to half speed motor3.run(BACKWARD); //rotate the motor clockwise motor4.setSpeed(127); //set motor4 to half speed motor4.run(BACKWARD); } void left() { motor1.setSpeed(127); //set motor1 to half speed max speed=255, min speed=0,half speed=127 motor1.run(BACKWARD); //rotate the motor clockwise motor2.setSpeed(127); //set motor2 to half speed motor2.run(BACKWARD); //rotate the motor clockwise motor3.setSpeed(127); //set motor3 to half speed motor3.run(FORWARD); //rotate the motor clockwise motor4.setSpeed(127); //set motor4 to half speed motor4.run(FORWARD); } void right() { motor1.setSpeed(127); motor1.run(FORWARD); //rotate the motor clockwise motor2.setSpeed(127); //set motor2 to half speed motor2.run(FORWARD); //rotate the motor clockwise motor3.setSpeed(127); //set motor3 to half speed motor3.run(BACKWARD); //rotate the motor clockwise motor4.setSpeed(127); //set motor4 to half speed motor4.run(BACKWARD); }

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