#include <LiquidCrystal.h>

#include <stdio.h>

#include <SoftwareSerial.h>

SoftwareSerial mySerial(8, 9);

LiquidCrystal lcd(6, 7, 5, 4, 3, 2);

#include <Wire.h>

#include "dht.h"

const int trigPin = A4;

const int echoPin = A3;

int m1a = 10;

int m1b = 11;

int m2a = 12;

int m2b = 13;

#define dht\_apin A2

dht DHT;

int buzzer = A5;

int tempc=0,humc=0;

int rtr1=0;

int dist1=0,dist2=0,dist3,sts1=0;

long duration;

int distanceCm, distanceInch;

unsigned char rcv,count,gchr='x',gchr1='x',robos='s';

char pastnumber[10];

char gpsval[50];

// char dataread[100] = "";

// char lt[15],ln[15];

int i=0,k=0;

int gps\_status=0;

float latitude=0;

float logitude=0;

String Speed="";

String gpsString="";

char \*test="$GPRMC";

int hbtc=0,hbtc1=0,rtrl=0;

unsigned char gv=0,msg1[10],msg2[11];

float lati=0,longi=0;

unsigned int lati1=0,longi1=0;

unsigned char flat[5],flong[5];

unsigned char finallat[8],finallong[9];

int ii=0;

float vout=0;

int sti=0;

String inputString = ""; // a string to hold incoming data

boolean stringComplete = false; // whether the string is complete

void okcheck()

{

unsigned char rcr;

do{

rcr = Serial.read();

}while(rcr != 'K');

}

unsigned int ultra\_dist()

{

digitalWrite(trigPin, LOW);

delayMicroseconds(5);

digitalWrite(trigPin, HIGH);

delayMicroseconds(10);

digitalWrite(trigPin, LOW);

duration = pulseIn(echoPin, HIGH);

distanceCm= duration\*0.034/2;

//distanceInch = duration\*0.0133/2;

//lcd.setCursor(2,0);

//convertl(distanceCm);

dist1 = distanceCm;

return dist1;

}

void send\_link()

{

Serial.write("AT+CMGS=\"");

Serial.write(pastnumber);

Serial.write("\"\r\n"); delay(2500);

Serial.write("https://www.google.co.in/search?client=opera&q=");

for(ii=0;ii<=6;ii++){Serial.write(finallat[ii]);}

Serial.write("%2C");

for(ii=0;ii<=7;ii++){Serial.write(finallong[ii]);}

Serial.write(0x1A);delay(4000);delay(4000);

}

void beep()

{

digitalWrite(buzzer, LOW);delay(2500); digitalWrite(buzzer, HIGH);

}

void serialFlush()

{

while(Serial.available() > 0)

{

char t = Serial.read();

}

}

void setup()

{

Serial.begin(9600);//serialEvent();

mySerial.begin(9600);

pinMode(trigPin, OUTPUT); // Sets the trigPin as an Output

pinMode(echoPin, INPUT); // Sets the echoPin as an Input

pinMode(m1a, OUTPUT);pinMode(m1b, OUTPUT);

pinMode(m2a, OUTPUT);pinMode(m2b, OUTPUT);

pinMode(buzzer, OUTPUT);

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

digitalWrite(buzzer, HIGH);

lcd.begin(16, 2);lcd.cursor();

lcd.print("GPS Controlled Env");

lcd.setCursor(0,1);

lcd.print(" Monitoring Robot ");

delay(1000);

get\_gps();

gps\_convert();

lcd.clear();

lcd.setCursor(0,0);

for(ii=0;ii<=6;ii++) lcd.write(finallat[ii]);

lcd.setCursor(0,1);

for(ii=0;ii<=7;ii++) lcd.write(finallong[ii]);

delay(1000);

//gsminit();

Serial.write("AT\r\n"); delay(2500);

Serial.write("ATE0\r\n"); okcheck();

Serial.write("AT+CWMODE=3\r\n"); delay(2500);// okcheck();

Serial.write("AT+CIPMUX=1\r\n"); delay(2500);// okcheck();

Serial.write("AT+CIPSERVER=1,23\r\n"); delay(2500);// okcheck();

do{

rcv = Serial.read();

}while(rcv != 'C');

lcd.clear();lcd.print(" Connected ");

delay(1500);

lcd.clear();

lcd.setCursor(0,0);

lcd.print("U:");//2-3-4,0

lcd.setCursor(6,0);

lcd.print("T:");//8-9-10,0

lcd.setCursor(11,0);

lcd.print("H:");//13-14-15,0

lcd.setCursor(0,1);

lcd.print("C:");//2-3-4,1

lcd.setCursor(8,1);

lcd.print("G:");//10,1

//serialEvent();

serialFlush();

}

char wifi\_data[20];

int co2v=0;

int gasv=0;

int cntlmk=0;

void loop()

{

for(rtr1=0;rtr1<5;rtr1++)

{

dist2 = ultra\_dist();

dist1 = (dist1 + dist2);

delay(10);

}

dist1 = (dist1/5);

lcd.setCursor(2,0);convertl(dist1);delay(10);

if(dist1 < 10)

{

sts1++;

if(sts1 >= 4)

{ sts1=0;

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

beep();

Serial.write("AT+CIPSEND=0,18\r\n");delay(2000);

Serial.write("U:");converts(dist1);Serial.write("-Obstacle\r\n");delay(3000);

Serial.write("AT+CIPSEND=0,21\r\n"); delay(2000);

Serial.write("GPS:");

for(ii=0;ii<=6;ii++) Serial.write(finallat[ii]);

for(ii=0;ii<=7;ii++) Serial.write(finallong[ii]);

Serial.write("\r\n"); delay(3000);

}

}

else

{

sts1=0;

}

DHT.read11(dht\_apin);

tempc = DHT.temperature;

humc = DHT.humidity;

lcd.setCursor(8,0);convertl(tempc);

lcd.setCursor(13,0);convertl(humc);

if(tempc > 40)

{

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

beep();

Serial.write("AT+CIPSEND=0,17\r\n");delay(2000);

Serial.write("High Temp:");converts(tempc);Serial.write("\r\n");delay(3000);

Serial.write("AT+CIPSEND=0,21\r\n"); delay(2000);

Serial.write("GPS:");

for(ii=0;ii<=6;ii++) Serial.write(finallat[ii]);

for(ii=0;ii<=7;ii++) Serial.write(finallong[ii]);

Serial.write("\r\n"); delay(3000);

}

if(humc > 75)

{

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

beep();

Serial.write("AT+CIPSEND=0,16\r\n");delay(2000);

Serial.write("High Hum:");converts(tempc);Serial.write("\r\n");delay(3000);

Serial.write("AT+CIPSEND=0,21\r\n"); delay(2000);

Serial.write("GPS:");

for(ii=0;ii<=6;ii++) Serial.write(finallat[ii]);

for(ii=0;ii<=7;ii++) Serial.write(finallong[ii]);

Serial.write("\r\n"); delay(3000);

}

co2v = analogRead(A0);

lcd.setCursor(2,1);convertl(co2v);

if(co2v > 150)

{

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

beep();

Serial.write("AT+CIPSEND=0,16\r\n");delay(2000);

Serial.write("High Co2:");converts(co2v);Serial.write("\r\n");delay(3000);

Serial.write("AT+CIPSEND=0,21\r\n"); delay(2000);

Serial.write("GPS:");

for(ii=0;ii<=6;ii++) Serial.write(finallat[ii]);

for(ii=0;ii<=7;ii++) Serial.write(finallong[ii]);

Serial.write("\r\n"); delay(3000);

}

gasv = analogRead(A1);

lcd.setCursor(10,1);convertl(gasv);

if(gasv > 150)

{

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

beep();

Serial.write("AT+CIPSEND=0,16\r\n");delay(2000);

Serial.write("High Gas:");converts(gasv);Serial.write("\r\n");delay(3000);

Serial.write("AT+CIPSEND=0,21\r\n"); delay(2000);

Serial.write("GPS:");

for(ii=0;ii<=6;ii++) Serial.write(finallat[ii]);

for(ii=0;ii<=7;ii++) Serial.write(finallong[ii]);

Serial.write("\r\n"); delay(3000);

}

/\*

if(stringComplete)

{

if(inputString[1] == 'f')

{

digitalWrite(m1a, HIGH);digitalWrite(m1b, LOW);

digitalWrite(m2a, HIGH);digitalWrite(m2b, LOW);

lcd.setCursor(15,1);lcd.print("F");

}

if(inputString[1] == 'b')

{

digitalWrite(m1a, LOW);digitalWrite(m1b, HIGH);

digitalWrite(m2a, LOW);digitalWrite(m2b, HIGH);

lcd.setCursor(15,1);lcd.print("B");

}

if(inputString[1] == 'l')

{

digitalWrite(m1a, HIGH);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, HIGH);

lcd.setCursor(15,1);lcd.print("L");

}

if(inputString[1] == 'r')

{

digitalWrite(m1a, LOW);digitalWrite(m1b, HIGH);

digitalWrite(m2a, HIGH);digitalWrite(m2b, LOW);

lcd.setCursor(15,1);lcd.print("R");

}

if(inputString[1] == 's')

{

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

lcd.setCursor(15,1);lcd.print("S");

}

inputString = "";

stringComplete = false;

}

\*/

while(Serial.available())

{

char inChar = (char)Serial.read();

if(inChar == '\*')

{sti=1;

}

if(sti == 1)

{

wifi\_data[cntlmk] = inChar;

cntlmk++;

}

if(inChar == '#')

{sti=0;

wifi\_data[cntlmk-1] = '\0';

cntlmk=0;

gchr = wifi\_data[1];

lcd.setCursor(15,1);lcd.write(gchr);

if(gchr == 'f')

{

digitalWrite(m1a, HIGH);digitalWrite(m1b, LOW);

digitalWrite(m2a, HIGH);digitalWrite(m2b, LOW);

delay(1500);

}

if(gchr == 'b')

{

digitalWrite(m1a, LOW);digitalWrite(m1b, HIGH);

digitalWrite(m2a, LOW);digitalWrite(m2b, HIGH);

delay(1500);

}

if(gchr == 'l')

{

digitalWrite(m1a, HIGH);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, HIGH);

delay(1500);

}

if(gchr == 'r')

{

digitalWrite(m1a, LOW);digitalWrite(m1b, HIGH);

digitalWrite(m2a, HIGH);digitalWrite(m2b, LOW);

delay(1500);

}

if(gchr == 's')

{

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

}

stringComplete = true;

inputString="";

}

}

}

/\*

void serialEvent()

{

while(Serial.available())

{

char inChar = (char)Serial.read();

if(inChar == '\*')

{sti=1;

}

if(sti == 1)

{

inputString += inChar;

}

if(inChar == '#')

{sti=0;

if(inputString[1] == 'f')

{inputString="";

digitalWrite(m1a, HIGH);digitalWrite(m1b, LOW);

digitalWrite(m2a, HIGH);digitalWrite(m2b, LOW);

lcd.setCursor(15,1);lcd.print("F");

}

if(inputString[1] == 'b')

{inputString="";

digitalWrite(m1a, LOW);digitalWrite(m1b, HIGH);

digitalWrite(m2a, LOW);digitalWrite(m2b, HIGH);

lcd.setCursor(15,1);lcd.print("B");

}

if(inputString[1] == 'l')

{inputString="";

digitalWrite(m1a, HIGH);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, HIGH);

lcd.setCursor(15,1);lcd.print("L");

}

if(inputString[1] == 'r')

{inputString="";

digitalWrite(m1a, LOW);digitalWrite(m1b, HIGH);

digitalWrite(m2a, HIGH);digitalWrite(m2b, LOW);

lcd.setCursor(15,1);lcd.print("R");

}

if(inputString[1] == 's')

{inputString="";

digitalWrite(m1a, LOW);digitalWrite(m1b, LOW);

digitalWrite(m2a, LOW);digitalWrite(m2b, LOW);

lcd.setCursor(15,1);lcd.print("S");

}

stringComplete = true;

inputString="";

}

}

}

\*/

/\*

void serialEvent()

{

while (Serial.available())

{

char inChar = (char)Serial.read();

if(inChar == '\*')

{

gchr = Serial.read();

}

if(inChar == '#')

{

gchr1 = Serial.read();

}

}

}\*/

int readSerial(char result[])

{

int i = 0;

while (1)

{

while (Serial.available() > 0)

{

char inChar = Serial.read();

if (inChar == '\n')

{

result[i] = '\0';

Serial.flush();

return 0;

}

if (inChar != '\r')

{

result[i] = inChar;

i++;

}

}

}

}

int readSerial1(char result[])

{

int i = 0;

while (1)

{

while (Serial.available() > 0)

{

char inChar = Serial.read();

if (inChar == '\*')

{

result[i] = '\0';

Serial.flush();

return 0;

}

if (inChar != '\*')

{

result[i] = inChar;

i++;

}

}

}

}

void gpsEvent()

{

gpsString="";

while(1)

{

//while (gps.available()>0) //Serial incoming data from GPS

while (mySerial.available() > 0)

{

//char inChar = (char)gps.read();

char inChar = (char)mySerial.read();

gpsString+= inChar; //store incoming data from GPS to temparary string str[]

i++;

// Serial.print(inChar);

if (i < 7)

{

if(gpsString[i-1] != test[i-1]) //check for right string

{

i=0;

gpsString="";

}

}

if(inChar=='\r')

{

if(i>60)

{

gps\_status=1;

break;

}

else

{

i=0;

}

}

}

if(gps\_status)

break;

}

}

void get\_gps()

{

lcd.clear();

lcd.print("Getting GPS Data");

lcd.setCursor(0,1);

lcd.print("Please Wait.....");

gps\_status=0;

int x=0;

while(gps\_status==0)

{

gpsEvent();

int str\_lenth=i;

coordinate2dec();

i=0;x=0;

str\_lenth=0;

}

}

void coordinate2dec()

{

String lat\_degree="";

for(i=19;i<=20;i++)

lat\_degree+=gpsString[i];

String lat\_minut="";

for(i=21;i<=22;i++)

lat\_minut+=gpsString[i];

for(i=24;i<=25;i++)

lat\_minut+=gpsString[i];

String log\_degree="";

for(i=32;i<=34;i++)

log\_degree+=gpsString[i];

String log\_minut="";

for(i=35;i<=36;i++)

log\_minut+=gpsString[i];

for(i=38;i<=39;i++)

log\_minut+=gpsString[i];

Speed="";

for(i=45;i<48;i++) //extract longitude from string

Speed+=gpsString[i];

float minut= lat\_minut.toFloat();

minut=minut/60;

float degree=lat\_degree.toFloat();

latitude=degree+minut;

minut= log\_minut.toFloat();

minut=minut/60;

degree=log\_degree.toFloat();

logitude=degree+minut;

}

void gps\_convert()

{

if(gps\_status)

{

// Serial.println(gpsString);

if(gpsString[0] == '$' && gpsString[1] == 'G' && gpsString[2] == 'P' && gpsString[3] == 'R' && gpsString[4] == 'M' && gpsString[5] == 'C')

{

// Serial.println("Don11111111111111111111111111111111111111111111111111111\r\n");

// Serial.write(gpsString[18]);Serial.write(gpsString[19]);Serial.write(gpsString[20]);Serial.write(gpsString[21]);Serial.write(gpsString[22]);

//lcd.setCursor(0,0);

for(ii=0;ii<9;ii++)

{

//lcd.write(gpsString[19+ii]);

msg1[ii] = gpsString[19+ii];

//Serial.write(msg1[ii]);

}

//Serial.println("\r\n");

//lcd.setCursor(0,1);

for(ii=0;ii<10;ii++)

{

//lcd.write(gpsString[32+ii]);

msg2[ii] = gpsString[32+ii];

// Serial.write(msg2[ii]);

}

// Serial.println(msg1);

// Serial.println(msg2);

//lati = (((msg1[2]-48)\*100000) +((msg1[3]-48)\*10000) + ((msg1[5]-48)\*1000) + ((msg1[6]-48)\*100) + ((msg1[7]-48)\*10) + (msg1[8]-48));

//longi = (((msg2[3]-48)\*100000) + ((msg2[4]-48)\*10000) + ((msg2[6]-48)\*1000) + ((msg2[7]-48)\*100) + ((msg2[8]-48)\*10) + (msg2[9]-48));

lati = (((msg1[2]-48)\*1000) + ((msg1[3]-48)\*100) + ((msg1[5]-48)\*10) + (msg1[6]-48));

longi = (((msg2[3]-48)\*1000) + ((msg2[4]-48)\*100) + ((msg2[6]-48)\*10) + (msg2[7]-48));

// converts(lati);Serial.write("-");

// converts(longi);Serial.write("\r\n");

lati = (lati/60); longi = (longi/60);

lati = (lati\*100); longi = (longi\*100);

lati1 = lati; longi1 = longi;

// Serial.write("After ");

// converts(lati1);Serial.write("-");

// converts(longi1);Serial.write("\r\n");

convlat(lati); convlong(longi);

finallat[0] = msg1[0];

finallat[1] = msg1[1];

finallat[2] = '.';

finallat[3] = flat[0]; finallat[4] = flat[1];finallat[5] = flat[2];finallat[6] = flat[3];finallat[7] = '\0';

finallong[0] = msg2[0];

finallong[1] = msg2[1];

finallong[2] = msg2[2];

finallong[3] = '.';

finallong[4] = flong[0];finallong[5] = flong[1];finallong[6] = flong[2];finallong[7] = flong[3];finallong[8] = '\0';

}

}

}

void convlat(unsigned int value)

{

unsigned int a,b,c,d,e,f,g,h;

a=value/10000;

b=value%10000;

c=b/1000;

d=b%1000;

e=d/100;

f=d%100;

g=f/10;

h=f%10;

a=a|0x30;

c=c|0x30;

e=e|0x30;

g=g|0x30;

h=h|0x30;

// dlcd(a);

// dlcd(c);dlcd(e); dlcd(g);dlcd(h);//lcddata('A');//lcddata(' ');lcddata(' ');

flat[0] = c;

flat[1] = e;

flat[2] = g;

flat[3] = h;

}

void convlong(unsigned int value)

{

unsigned int a,b,c,d,e,f,g,h;

a=value/10000;

b=value%10000;

c=b/1000;

d=b%1000;

e=d/100;

f=d%100;

g=f/10;

h=f%10;

a=a|0x30;

c=c|0x30;

e=e|0x30;

g=g|0x30;

h=h|0x30;

// dlcd(a);

// dlcd(c);dlcd(e); dlcd(g);dlcd(h);//lcddata('A');//lcddata(' ');lcddata(' ');

flong[0] = c;

flong[1] = e;

flong[2] = g;

flong[3] = h;

}

/\*

void coordinate2dec()

{

String lat\_degree="";

for(i=20;i<=21;i++)

lat\_degree+=gpsString[i];

String lat\_minut="";

for(i=22;i<=28;i++)

lat\_minut+=gpsString[i];

String log\_degree="";

for(i=32;i<=34;i++)

log\_degree+=gpsString[i];

String log\_minut="";

for(i=35;i<=41;i++)

log\_minut+=gpsString[i];

Speed="";

for(i=45;i<48;i++) //extract longitude from string

Speed+=gpsString[i];

float minut= lat\_minut.toFloat();

minut=minut/60;

float degree=lat\_degree.toFloat();

latitude=degree+minut;

minut= log\_minut.toFloat();

minut=minut/60;

degree=log\_degree.toFloat();

logitude=degree+minut;

}\*/

void gsminit()

{

Serial.write("AT\r\n"); okcheck();

Serial.write("ATE0\r\n"); okcheck();

Serial.write("AT+CMGF=1\r\n"); okcheck();

Serial.write("AT+CNMI=1,2,0,0\r\n"); okcheck();

Serial.write("AT+CSMP=17,167,0,0\r\n"); okcheck();

lcd.clear();

lcd.print("SEND MSG STORE");

lcd.setCursor(0,1);

lcd.print("MOBILE NUMBER");

do{

rcv = Serial.read();

}while(rcv != '\*');

readSerial(pastnumber);

lcd.clear();

lcd.print(pastnumber);

Serial.write("AT+CMGS=\"");

Serial.write(pastnumber);

Serial.write("\"\r\n"); delay(3000);

Serial.write("Mobile no. registered\r\n");

Serial.write(0x1A);

//pastnumber[10]='\0';

delay(4000);

//delay(1000);

}

/\*

int gpsgain(char result[])

{

int i = 0;

char rcvv;

while (1)

{

while (Serial.available() > 0)

{

lp:

char inChar = Serial.read();

result[i] = inChar;

if(result[0] == '$')

{

i++;

// result[i] = inChar;

}

if(result[0] != '$')

{

i=0;

}

if(i == 5)

{

if(result[0] == '$' && result[1] == 'G' && result[2] == 'P' && result[3] == 'R' && result[4] == 'M' && result[5] == 'C')

{

goto lp;

}

else

{

i=0;

}

}

if(i == 46)

{

result[47] = '\0';

Serial.flush();

lt[0]=result[21];lt[1]=result[22];lt[2]=result[23];lt[3]=result[24];lt[4]=result[25];lt[5]=result[26];

lt[6]=result[27];lt[7]=result[28];lt[8]=result[29];lt[9]=result[30];lt[10]=result[31];lt[11]='\0';

ln[0]=result[33];ln[1]=result[34];ln[2]=result[35];ln[3]=result[36];ln[4]=result[37];ln[5]=result[38];

ln[6]=result[39];ln[7]=result[40];ln[8]=result[41];ln[9]=result[42];ln[10]=result[43];ln[11]=result[44];ln[12]='\0';

return 0;

}

}

}

}

\*/

/\*

void keypad()

{

char kn=0,valk=0;

lcd.setCursor(0,1);

while(1)

{

if(digitalRead(swi) == LOW)

{delay(1000);

while(digitalRead(swi) == LOW);

valk++;

if(valk >= 9)

{

valk=9;

}

lcd.setCursor(kn,1); convertk(valk);

}

if(digitalRead(swd) == LOW)

{delay(1000);

while(digitalRead(swd) == LOW);

valk--;

if(valk <= 0)

{

valk=0;

}

lcd.setCursor(kn,1); convertk(valk);

}

if(digitalRead(swe) == LOW)

{delay(1000);

while(digitalRead(swe) == LOW);

password[kn] = (valk+48);

kn++;

lcd.setCursor(kn,1);

valk=0;

if(kn == 4)

{kn=0;

break;

}

}

}

}

\*/

void converts(unsigned int value)

{

unsigned int a,b,c,d,e,f,g,h;

a=value/10000;

b=value%10000;

c=b/1000;

d=b%1000;

e=d/100;

f=d%100;

g=f/10;

h=f%10;

a=a|0x30;

c=c|0x30;

e=e|0x30;

g=g|0x30;

h=h|0x30;

Serial.write(a);

Serial.write(c);

Serial.write(e);

Serial.write(g);

Serial.write(h);

}

void convertl(unsigned int value)

{

unsigned int a,b,c,d,e,f,g,h;

a=value/10000;

b=value%10000;

c=b/1000;

d=b%1000;

e=d/100;

f=d%100;

g=f/10;

h=f%10;

a=a|0x30;

c=c|0x30;

e=e|0x30;

g=g|0x30;

h=h|0x30;

//lcd.write(a);

//lcd.write(c);

lcd.write(e);

lcd.write(g);

lcd.write(h);

}

void convertk(unsigned int value)

{

unsigned int a,b,c,d,e,f,g,h;

a=value/10000;

b=value%10000;

c=b/1000;

d=b%1000;

e=d/100;

f=d%100;

g=f/10;

h=f%10;

a=a|0x30;

c=c|0x30;

e=e|0x30;

g=g|0x30;

h=h|0x30;

// lcd.write(a);

// lcd.write(c);

// lcd.write(e);

// lcd.write(g);

lcd.write(h);

}