#include <Servo.h>

const int ldrPin = A0;

const int tmpPin = A1;

const int motor = 10;

const int light = 9;

const int light2 = 7;

const int led = 4;

int rip = 0;

int servo = 0;

Servo servo\_11;

int i;

void setup() {

pinMode(ldrPin, INPUT);

pinMode(tmpPin, INPUT);

pinMode(motor, OUTPUT);

pinMode(light, OUTPUT);

pinMode(light2, OUTPUT);

pinMode(led, OUTPUT);

Serial.begin(9600);

pinMode(12, INPUT);

pinMode(11, INPUT);

servo\_11.attach(11, 500, 2500);

}

void loop() {

int ldrStatus = analogRead(ldrPin);

int tmpStatus = analogRead(tmpPin);

Serial.print("LDR");

Serial.print("TMP");

Serial.println(ldrStatus);

Serial.println(tmpStatus);

Serial.println(rip);

rip = digitalRead(12);

servo = digitalRead(11);

if (rip == 1) {

servo\_11.write(180);

} else {

servo\_11.write(0);

}

if (-40 + 0.488155 \* (tmpStatus - 20) > 28 ) {

analogWrite(motor,255);

} else {

analogWrite(motor,0);

}

if (ldrStatus> 610 && ldrStatus<=679 ) {

analogWrite(light,0);

analogWrite(light2,0);

for(i=0;i<=12;i++)

{

analogWrite(led,255);

delay(500);

analogWrite(led,0);

}

}

else if(ldrStatus> 544 && ldrStatus<=610 ){

analogWrite(light,255);

analogWrite(light2,0);

analogWrite(led,0);

}

else if(ldrStatus> 409 && ldrStatus<=544 ){

analogWrite(light,255);

analogWrite(light2,0);

analogWrite(led,0);

}

else if(ldrStatus> 274 && ldrStatus<=409){

analogWrite(light,255);

analogWrite(light2,0);

analogWrite(led,0);

}

else if(ldrStatus>=139 && ldrStatus<=274 ){

analogWrite(light,255);

analogWrite(light2,0);

analogWrite(led,0);

}

else if(ldrStatus >= 6 && ldrStatus<=139 ){

analogWrite(light,255);

analogWrite(light2,255);

analogWrite(led,0);

delay(1000);

}

}