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#include "DHT.h"
#include "Servo.h"

const int basicServo1WritePin1 = 12;
const int humidityandTemperatureSensorRHT031ReadPin1 = 6;
const int tS2ReadPin1 = 3;
const int infrared850nmLED1WritePin1 = 2;
const int tS1ReadPin1 = 10;
const int infrared850nmLED2WritePin1 = 9;
const int basicServo2WritePin1 = 13;
const int red633nmLED1WritePin1 = 7;

int irLeft, irRight;
int humPin = 6;
int ledPin = 8;
float humThresh = 25.0;

void setup() {
  low(26);
  low(27);
  drive_setRampStep(12);
}

void loop() {
  dht22_read(humPin);
  float humidity = dht22_getHumidity();
  humidity = humidity / 10.0;
  float temp = dht22_getTemp(CELSIUS) / 10.0;
  myPrintf(humidity);
  putchar('\n');
  myPrintf(temp);
  putchar('\n');
  if(temp > humThresh) {
    high(ledPin);
  } else {
    low(ledPin);
  }
  freqout(11, 1, 38000);
  irLeft = input(10);
  freqout(1, 1, 38000);
  irRight = input(2);
  if(irRight == 1 && irLeft == 1) {
    drive_rampStep(128, 128);
  } else if(irLeft == 0 && irRight == 0) {
    drive_rampStep(-128, -128);
  } else if(irRight == 0) {
    drive_rampStep(-128, 128);
  } else if(irLeft == 0) {
    drive_rampStep(128, -128);
  }
}

void myPrintf(float fVal)
{
  char result[100];
  int dVal, dec, i;

  fVal += 0.005;

  dVal = fVal;
  dec = (int)(fVal * 100) % 100;

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memset(result, 0, 100);
result[0] = (dec % 10) + '0';
result[1] = (dec / 10) + '0';
result[2] = '.';

i = 3;
while (dVal > 0)
{
    result[i] = (dVal % 10) + '0';
    dVal /= 10;
    i++;
}

for (i=strlen(result)-1; i>=0; i--) {
    putc(result[i], stdout);
}
}

char dht22_read(int dht_pin) {
    // TODO: complete method
}

int dht22_getHumidity() {
    // TODO: complete method
}

void high(int pin) {
    // TODO: complete method
}

void freqout(int pin, int msTime, int frequency) {
    // TODO: complete method
}

int input(int pin) {
    // TODO: complete method
}

void drive_rampStep(int left, int right) {
    // TODO: complete method
}

int dht22_getTemp(char temp_units) {
    // TODO: complete method
}

void low(int pin) {
    // TODO: complete method
}

void drive_setRampStep(int stepsize) {
    // TODO: complete method
}

```