//viral science

//voice controlled car

#include <AFMotor.h>

#include <Servo.h>

String voice;

AF\_DCMotor motor1 (1, MOTOR12\_1KHZ);

AF\_DCMotor motor2 (2, MOTOR12\_1KHZ);

Servo myServo;

void setup()

{

Serial.begin(9600);

myServo.attach(10);

myServo.write(90);

}

void loop()

{

while (Serial.available()){

delay(10);

char c = Serial.read();

if (c == '#') {break;}

voice += c;

}

if (voice.length() > 0){

if(voice == "\*go ahead"){

forward\_car();

}

else if(voice == "\*go back"){

back\_car();

}

else if(voice == "\*right") {

right\_car();

}

else if(voice == "\*left") {

left\_car();

}

else if(voice == "\*stop") {

stop\_car();

}

voice="";

}

}

void forward\_car()

{

motor1.run(FORWARD);

motor1.setSpeed(700);

motor2.run(FORWARD);

motor2.setSpeed(700);

delay(2000);

motor1.run(RELEASE);

motor2.run(RELEASE);

}

void back\_car()

{

motor1.run(BACKWARD);

motor1.setSpeed(700);

motor2.run(BACKWARD);

motor2.setSpeed(700);

delay(2000);

motor1.run(RELEASE);

motor2.run(RELEASE);

}

void right\_car()

{

myServo.write(0);

delay(1000);

myServo.write(90);

delay(1000);

motor1.run(FORWARD);

motor1.setSpeed(190);

motor2.run(BACKWARD);

motor2.setSpeed(190);

delay(1000);

motor1.run(RELEASE);

motor2.run(RELEASE);

}

void left\_car()

{

myServo.write(180);

delay(1000);

myServo.write(90);

delay(1000);

motor1.run(BACKWARD);

motor1.setSpeed(190);

motor2.run(FORWARD);

motor2.setSpeed(190);

delay(1000);

motor1.run(RELEASE);

motor2.run(RELEASE);

}

void stop\_car ()

{

motor1.run(RELEASE);

motor2.run(RELEASE);

}