// Motor A connections

int enA = 9;

int in1 = 8;

int in2 = 7;

// Motor B connections

int enB = 3;

int in3 = 5;

int in4 = 4;

void setup()

{

// Set all the motor control pins to outputs

pinMode(enA, OUTPUT);

pinMode(enB, OUTPUT);

pinMode(in1, OUTPUT);

pinMode(in2, OUTPUT);

pinMode(in3, OUTPUT);

pinMode(in4, OUTPUT);

// Turn off motors - Initial state

digitalWrite(in1, LOW);

digitalWrite(in2, LOW);

digitalWrite(in3, LOW);

digitalWrite(in4, LOW);

}

void loop()

{

directionControl();

delay(1000);

speedControl();

delay(1000);

}

// This function lets you control spinning direction of motors

void directionControl()

{

// Set motors to maximum speed

// For PWM maximum possible values are 0 to 255

analogWrite(enA, 255);

analogWrite(enB, 255);

// Turn on motor A & B

digitalWrite(in1, HIGH);

digitalWrite(in2, LOW);

digitalWrite(in3, HIGH);

digitalWrite(in4, LOW);

delay(2000);

// Now change motor directions

digitalWrite(in1, LOW);

digitalWrite(in2, HIGH);

digitalWrite(in3, LOW);

digitalWrite(in4, HIGH);

delay(2000);

// Turn off motors

digitalWrite(in1, LOW);

digitalWrite(in2, LOW);

digitalWrite(in3, LOW);

digitalWrite(in4, LOW);

}

// This function lets you control speed of the motors

void speedControl()

{

// Turn on motors

digitalWrite(in1, LOW);

digitalWrite(in2, HIGH);

digitalWrite(in3, LOW);

digitalWrite(in4, HIGH);

// Accelerate from zero to maximum speed

for (int i = 0; i < 256; i++)

{

analogWrite(enA, i);

analogWrite(enB, i);

delay(20);

}

// Decelerate from maximum speed to zero

for (int i = 255; i >= 0; --i)

{

analogWrite(enA, i);

analogWrite(enB, i);

delay(20);

}

// Now turn off motors

digitalWrite(in1, LOW);

digitalWrite(in2, LOW);

digitalWrite(in3, LOW);

digitalWrite(in4, LOW);

}