**MOTOR CONTROL WITH L298N Motor Bridge and Arduino**

int enA = 9;

int enB = 3;

int in1 = 8;

int in2 = 7;

int in3 = 5;

int in4 = 4;

void go\_Forward (void){

digitalWrite(in1, HIGH);

digitalWrite(in2, LOW);

digitalWrite(in3, HIGH);

digitalWrite(in4, LOW);

}

void go\_Left (void){

digitalWrite(in1, HIGH);

digitalWrite(in2, LOW);

digitalWrite(in3, LOW);

digitalWrite(in4, HIGH);

}

void go\_Right (void){

digitalWrite(in1, LOW);

digitalWrite(in2, HIGH);

digitalWrite(in3, HIGH);

digitalWrite(in4, LOW);

}

void go\_Back (void){

digitalWrite(in1, LOW);

digitalWrite(in2, HIGH);

digitalWrite(in3, LOW);

digitalWrite(in4, HIGH);

}

void stop\_stop (void){

digitalWrite(in1, LOW);

digitalWrite(in2, LOW);

digitalWrite(in3, LOW);

digitalWrite(in4, LOW);

}

void set\_Motorspeed(int speed\_L, int speed\_R){

analogWrite(enA, speed\_L);

analogWrite(enB, speed\_R);

}

void setup

() {

// put your setup code here, to run once:

pinMode(enA, OUTPUT);

pinMode(enB, OUTPUT);

pinMode(in1, OUTPUT);

pinMode(in2, OUTPUT);

pinMode(in3, OUTPUT);

pinMode(in4, OUTPUT);

go\_Forward();

set\_Motorspeed(255,255);

delay(5000);

go\_Back();

set\_Motorspeed(255,255);

delay(5000);

go\_Left();

set\_Motorspeed(255,255);

delay(5000);

go\_Right();

set\_Motorspeed(255,255);

delay(5000);

stop\_stop();

}

void loop() {

// put your main code here, to run repeatedly:

}