

## **BASIC LINE FOLLOWER PROGRAM USING 2 IR SENSOR AND 2 PROXIMITY SENSOR WITH DIGITAL O/P**

**void setup()**

```
{  
  pinMode(2, INPUT);           // RIGHT IR  
  pinMode(3, INPUT);           // LEFT IR  
  pinMode(4, INPUT);           // LEFT PROXIMITY  
  pinMode(7, INPUT);           // RIGHT PROXIMITY  
  pinMode(5, OUTPUT);          // RIGHT MOTOR  
  pinMode(6, OUTPUT);          // RIGHT MOTOR  
  pinMode(10, OUTPUT);         // LEFT MOTOR  
  pinMode(11, OUTPUT);         // LEFT MOTOR  
  pinMode(13, OUTPUT);         // LED  
}
```

**void forward()**

```
{  
  digitalWrite(5,HIGH);  
  digitalWrite(6,LOW);  
  digitalWrite(10,HIGH);  
  digitalWrite(11,LOW);  
}
```

**void right()**

```
{  
  digitalWrite(5,LOW);  
  digitalWrite(6,LOW);  
  digitalWrite(10,HIGH);  
  digitalWrite(11,LOW);  
}
```

**void left()**

```
{  
  digitalWrite(5,HIGH);  
  digitalWrite(6,LOW);  
  digitalWrite(10,LOW);  
  digitalWrite(11,LOW);  
}
```

**void stp()**

```
{  
  digitalWrite(5,LOW);  
  digitalWrite(6,LOW);  
  digitalWrite(10,LOW);  
  digitalWrite(11,LOW);  
}
```

**void lf()**

```
{  
  int rir = digitalRead(2);  
  int lir = digitalRead(3);  
  
  if (rir == LOW && lir == LOW)  
  {  
    forward();  
  }  
  else if (rir == HIGH && lir == LOW)  
  {  
    right();  
  }  
  else if (rir == LOW && lir == HIGH)  
  {  
    left();  
  }  
}
```

```
/* else if (rir == HIGH && lir == HIGH)
{
    ACCORDING TO THE PROBLEM STATEMENT
} */
}
```

### **void loop()**

```
{
    int rir = digitalRead(2);
    int lir = digitalRead(3);
    int lps = digitalRead(4);
    int rps = digitalRead(7);

    if (lps == HIGH && rps == HIGH)
    {
        digitalWrite(13, HIGH);
        stp();
    }
    else if (lps == LOW && rps == HIGH)
    {
        digitalWrite(13, HIGH);
    }
    else if (lps == HIGH && rps == LOW)
    {
        digitalWrite(13, HIGH);
    }
    else if (lps == LOW && rps == LOW)
    {
        digitalWrite(13, LOW);
        lf();
    }
}
```

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