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int ENA = 9; //ENA connected to digital pin 9
int ENB = 3; //ENB connected to digital pin 3
int MOTOR_A1 = 7; // MOTOR_A1 connected to digital pin 7
int MOTOR_A2 = 6; // MOTOR_A2 connected to digital pin 6
int MOTOR_B1 = 5; // MOTOR_B1 connected to digital pin 5
int MOTOR_B2 = 4; // MOTOR_B2 connected to digital pin 4


int RIGHT = A0; // RIGHT sensor connected to analog pin A0
int LEFT = A1; // LEFT sensor connected to analog pin A1


// the setup function runs once when you press reset or power the board
void setup() {

  pinMode(ENA, OUTPUT); // initialize ENA pin as an output
  pinMode(ENB, OUTPUT); // initialize ENB pin as an output
  pinMode(MOTOR_A1, OUTPUT); // initialize MOTOR_A1 pin as an output
  pinMode(MOTOR_A2, OUTPUT); // initialize MOTOR_A2 pin as an output
  pinMode(MOTOR_B1, OUTPUT); // initialize MOTOR_B1 pin as an output
  pinMode(MOTOR_B2, OUTPUT); // initialize MOTOR_B2 pin as an output
  pinMode(RIGHT, INPUT); // initialize RIGHT pin as an input
  pinMode(LEFT, INPUT); // initialize ENA pin as an input

}


// the loop function runs over and over again forever
void loop() {

  if (analogRead(RIGHT)<=35 && analogRead(LEFT)<=35) //compare the both
  sensor to decide the direction
  {
    //MOVE FORWARD//
  }
}

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analogWrite(ENA, 100); // set right motors speed
analogWrite(ENB, 100); // set left motors speed

//run right motors clockwise
digitalWrite(MOTOR_A1, LOW);
digitalWrite(MOTOR_A2, HIGH);
//run left motors clockwise
digitalWrite(MOTOR_B1, HIGH);
digitalWrite(MOTOR_B2, LOW);
}
else if (analogRead(RIGHT)<=35 && !analogRead(LEFT)<=35) //compare the
both sensor to decide the direction
{
    //MOVE RIGHT//

    analogWrite(ENA, 255); //set right motors speed
    analogWrite(ENB, 255); //set left motors speed

    //run right motors clockwise
    digitalWrite(MOTOR_A1, LOW);
    digitalWrite(MOTOR_A2, HIGH);
    //run left motors anti-clockwise
    digitalWrite(MOTOR_B1, LOW);
    digitalWrite(MOTOR_B2, HIGH);
}
else if (!analogRead(RIGHT)<=35 && analogRead(LEFT)<=35) //compare the
both sensor to decide the direction
{
    //MOVE-LEFT//

    analogWrite(ENA, 255); //set right motors speed
    analogWrite(ENB, 255); //set left motors speed

    //run right motors anti-clockwise
    digitalWrite(MOTOR_A1, HIGH);
    digitalWrite(MOTOR_A2, LOW);
    //run left motors clockwise
    digitalWrite(MOTOR_B1, HIGH);
    digitalWrite(MOTOR_B2, LOW);
}

```

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}  
else if (!analogRead(RIGHT)<=35 && !analogRead(LEFT)<=35) //compare the  
both sensor to decide the direction  
{  
    //STOP//  
  
    analogWrite(ENA, 0); //set right motors speed  
    analogWrite(ENB, 0); //set left motors speed  
  
    //stop right motors  
    digitalWrite(MOTOR_A1, LOW);  
    digitalWrite(MOTOR_A2, LOW);  
    //stop left motors  
    digitalWrite(MOTOR_B1, LOW);  
    digitalWrite(MOTOR_B2, LOW);  
}  
}
```