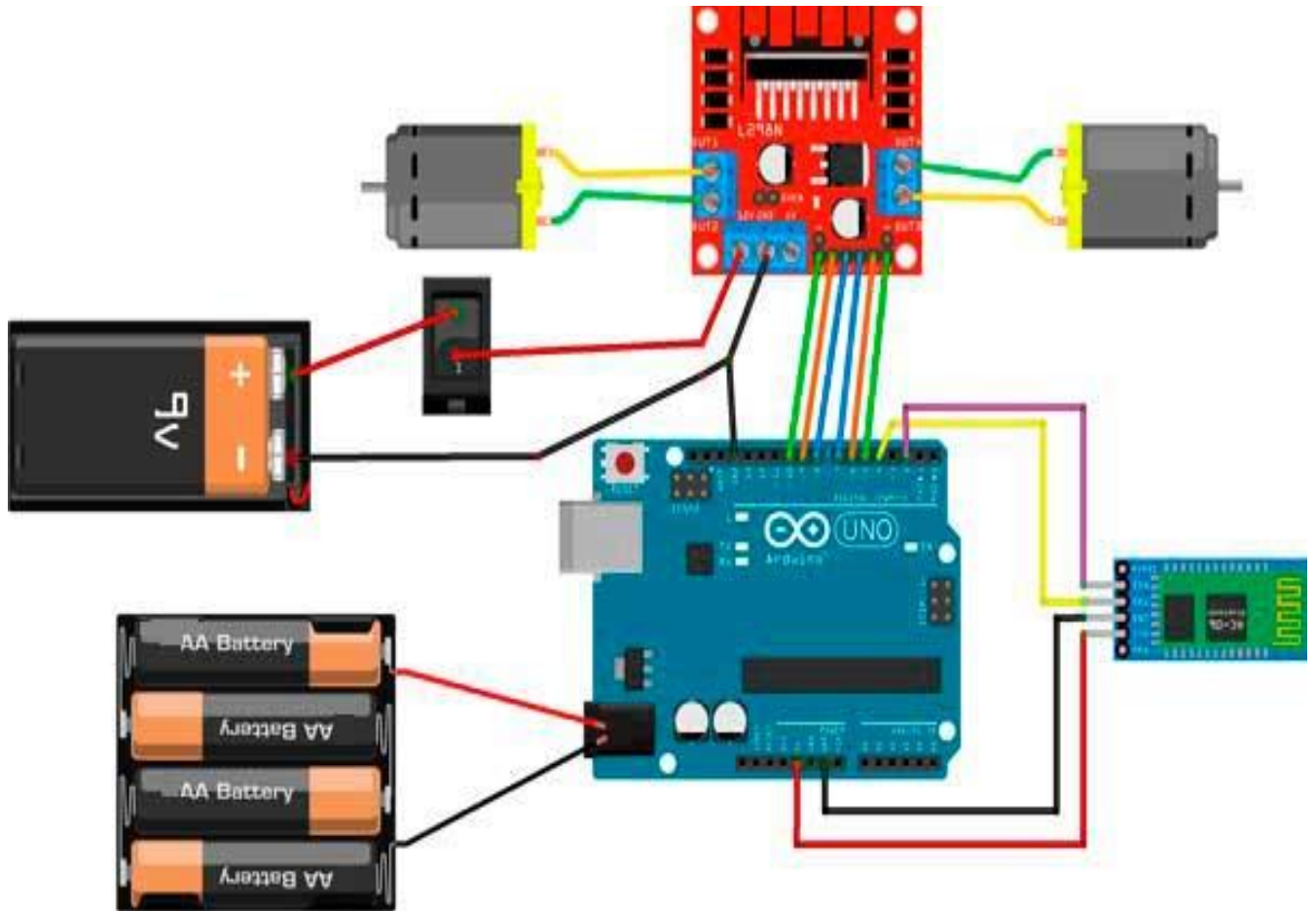


برنامج الروبوت المتحرك والمتحكم به بواسطة ال: Bluetooth



Arduino Code:

```
#include <SoftwareSerial.h>
#include <Wire.h>
#include <SoftwareSerial.h>
double angle_rad = PI/180.0;
double angle_deg = 180.0/PI;
```

```
SoftwareSerial hc06(4,2);
String cmd="";
// Moteur 1
```

```

//int ENA = 10;
int IN1 = 9;
int IN2 = 8;

// Moteur 2
//int ENB = 5;
int IN3 = 7;
int IN4 = 6;

void setup() {
  Serial.begin(9600);
  hc06.begin(9600);

  // pinMode (ENA, OUTPUT);
  // pinMode (ENB, OUTPUT);
  pinMode (IN1, OUTPUT);
  pinMode (IN2, OUTPUT);
  pinMode (IN3, OUTPUT);
  pinMode (IN4, OUTPUT);
}

void loop() {
  while(hc06.available()>0){
    cmd+=(char)hc06.read();
  }

  //Select function with cmd
  if(cmd!=""){
    Serial.print("Command recieved : ");
    Serial.println(cmd);
    // We expect ON or OFF from bluetooth
    if(cmd=="avant"){

      //Direction moteur A
      digitalWrite (IN1, HIGH);
      digitalWrite (IN2, LOW);
      //analogWrite (ENA, 255); //Vitesse moteur A
      //Direction moteur B
      digitalWrite (IN3, HIGH);
      digitalWrite (IN4, LOW);
      //analogWrite (ENB, 255); //Vitesse moteur B

    }
    if(cmd=="arriere"){

      //Direction moteur A
      digitalWrite (IN1, LOW);
      digitalWrite (IN2, HIGH);
      // analogWrite (ENA, 255); //Vitesse moteur A
      //Direction moteur B
      digitalWrite (IN3, LOW);
      digitalWrite (IN4, HIGH);
    }
  }
}

```

```

//analogWrite (ENB, 255); //Vitesse moteur B

}
if(cmd=="gauche"){

//Direction moteur A
digitalWrite (IN1, HIGH);
digitalWrite (IN2, LOW);
//analogWrite (ENA, 100); //Vitesse moteur A
//Direction moteur B
digitalWrite (IN3, LOW);
digitalWrite (IN4, LOW);
//analogWrite (ENB, 100); //Vitesse moteur A
}
if(cmd=="droite"){
//Direction moteur A
digitalWrite (IN1, LOW);
digitalWrite (IN2, LOW);
//analogWrite (ENA, 100); //Vitesse moteur A
//Direction moteur B
digitalWrite (IN3, HIGH);
digitalWrite (IN4, LOW);
//analogWrite (ENB, 100); //Vitesse moteur B
}
if(cmd=="stop"){
//Direction moteur A
digitalWrite (IN1, LOW);
digitalWrite (IN2, LOW);
//analogWrite (ENA, 0); //Vitesse moteur A
//Direction moteur B
digitalWrite (IN3, LOW);
digitalWrite (IN4, LOW);
//analogWrite (ENB, 0); //Vitesse moteur A
}
cmd=""; //reset cmd
}

delay(100);
}

```

AppInventor Code

