// Ardublockly generated sketch

#include <Ultrasonic.h>

boolean meio;

void forward(int MotA, int MotB)

{

analogWrite(10,MotA);//Motor A vel

analogWrite(11,MotB);//Motor B vel

digitalWrite(13,LOW);// Motor B (direito) move no sentido do relogio

digitalWrite(12,LOW);//Motor A (esquerda) move no sentido do relogio

}

Ultrasonic ultrasonic\_15(15,16);

void stop()

{

analogWrite(10,0);//Motor A vel

analogWrite(11,0);//Motor B vel

}

void backward(int MotA, int MotB)

{

analogWrite(10,MotA);//Motor A vel

analogWrite(11,MotB);//Motor B vel

digitalWrite(13,HIGH);// Motor B (direito) move no sentido contrario do relogio

digitalWrite(12,HIGH);//Motor A (esquerda) move no sentido contrario do relogio

}

void right(int MotA, int MotB)

{

analogWrite(10,MotA);//Motor A vel

analogWrite(11,MotB);//Motor B vel

digitalWrite(13,HIGH);//Motor B (direito) move no sentido do relogio

digitalWrite(12,LOW);//Motor A (esquerda) move no sentido contrario do relogio

}

void setup() {

pinMode(17, INPUT);

pinMode(12,OUTPUT);//direcaoPinoA

pinMode(13,OUTPUT);//direcaoPinoB

pinMode(10,OUTPUT);//velPinoA

pinMode(11,OUTPUT);//velPinoB

pinMode(4, OUTPUT);

}

void loop() {

meio = (boolean)(digitalRead(17));

forward(250, 250);

if (ultrasonic\_15.convert(ultrasonic\_15.timing(),Ultrasonic::CM) < 20) {

stop();

delay(1000);

backward(200, 200);

delay(1000);

right(200, 127);

delay(500);

}

if (!meio) {

stop();

//delay(2000);

tone(4,220);

delay(200);

tone(4,210);

delay(200);

tone(4,220);

delay(200);

tone(4,210);

delay(200);

noTone(4);

forward(250,250);

delay(1000);

}

}