

```

/*
  ROBOT ESQUIVA OBJETOS
  Programa que gestiona el funcionamiento del robot esquivo objetos
*/

int motl= 2;
int motr= 3;
int senr= 1;
int senl= 2;
int valizq= 0;
int valder= 0;
void setup()
{
  pinMode(motl, OUTPUT);
  pinMode(motr, OUTPUT);
}

void adelante ()
{
  digitalWrite(motl,HIGH);
  delayMicroseconds(1000);
  digitalWrite(motl,LOW);
  digitalWrite(motr,HIGH);
  delayMicroseconds(2000);
  digitalWrite(motr,LOW);
  delayMicroseconds(20000);
}

void atras ()
{
  digitalWrite(motr,HIGH);
  delayMicroseconds(1000);
  digitalWrite(motr,LOW);
  digitalWrite(motl,HIGH);
  delayMicroseconds(2000);
  digitalWrite(motl,LOW);
  delayMicroseconds(20000);
}

void derecha ()
{
  digitalWrite(motl,HIGH);
  delayMicroseconds(2000);
  digitalWrite(motl,LOW);
  digitalWrite(motr,HIGH);
  delayMicroseconds(2000);
  digitalWrite(motr,LOW);
  delayMicroseconds(20000);
}

void izquierda ()
{

```

```
digitalWrite(motr,HIGH);
delayMicroseconds(2000);
digitalWrite(motr,LOW);
digitalWrite(motl,HIGH);
delayMicroseconds(2000);
digitalWrite(motl,LOW);
delayMicroseconds(20000);
}
```

```
void loop()
{
  valizq=analogRead (senl);
  valder=analogRead (senr);
  if (valder>400&&valizq>400)
  {
    atras();
  }
  else
  {
    if(valder>400)
    {
      izquierda();
    }
    else
    {
      if(valizq>400)
      {
        derecha();
      }
      else
      {
        adelante();
      }
    }
  }
}
```