int SPEED = 85;

int Left\_Sensor = A1;

int Right\_Sensor = A0;

void setup() {

 // put your setup code here, to run once:

 pinMode(2, OUTPUT);

 pinMode(3, OUTPUT);

 pinMode(4, OUTPUT);

 pinMode(6, OUTPUT);

 pinMode(7, OUTPUT);

 pinMode(8, OUTPUT);

}

void forward() {

 digitalWrite(2, LOW);

 digitalWrite(4, HIGH);

 analogWrite(3, SPEED);

 digitalWrite(7, HIGH);

 digitalWrite(8, LOW);

 analogWrite(6, SPEED);

}

void backward() {

 digitalWrite(2, HIGH);

 digitalWrite(4, LOW);

 analogWrite(3, SPEED);

 digitalWrite(7, LOW);

 digitalWrite(8, HIGH);

 analogWrite(6, SPEED);

}

void left() {

 digitalWrite(2, HIGH);

 digitalWrite(4, LOW);

 analogWrite(3, SPEED);

 digitalWrite(7, HIGH);

 digitalWrite(8, LOW);

 analogWrite(6, SPEED);

}

void right() {

 digitalWrite(2, LOW);

 digitalWrite(4, HIGH);

 analogWrite(3, SPEED);

 digitalWrite(7, LOW);

 digitalWrite(8, HIGH);

 analogWrite(6, SPEED);

}

void loop() {

 int ls\_read = analogRead(Left\_Sensor);

 int rs\_read = analogRead(Right\_Sensor);

 bool Right\_White = rs\_read < 600;

 bool Right\_Black = !Right\_White;

 bool Left\_White = ls\_read < 600;

 bool Left\_Black = !Left\_White;

 if (Left\_White && Right\_White) {

 forward();

 } else if (Left\_Black && Right\_Black) {

 left();

 delay(400);

 } else if (Left\_White && Right\_Black) {

 left();

 }

 else if (Left\_Black && Right\_White) {

 right();

 }

}

Ссылка [file:///C:/Users/bia/Downloads/1\_robot\_table%20(3).ino](file:///C%3A/Users/bia/Downloads/1_robot_table%20%283%29.ino)