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>