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#include <Servo.h>
Servo one;
// motor one
int enA = 11;
int in1 = 12;
int in2 = 8;
// motor two
int enB = 5;
int in3 = 7;
int in4 = 6;

const int FLEX_PIN1 = A2;
const int FLEX_PIN2 = A0;
const int FLEX_PIN3 = A3;
const int FLEX_PIN4 = A5;
int servoVal;
void setup()
{
  Serial.begin(9600);
  one.attach(9);
  pinMode(enA, OUTPUT);
  pinMode(enB, OUTPUT);
  pinMode(in1, OUTPUT);
  pinMode(in2, OUTPUT);
  pinMode(in3, OUTPUT);
  pinMode(in4, OUTPUT);
  pinMode(FLEX_PIN1, INPUT);
  pinMode(FLEX_PIN2, INPUT);
  pinMode(FLEX_PIN3, INPUT);
  pinMode(FLEX_PIN4, INPUT);
}
void main1()
{
  int flexADC1 = analogRead(FLEX_PIN1);
  float val1 = map(flexADC1, 607, 832, 18, 0); //maps a value between 0 and 18 based on the angle of the flex sensor

  int flexADC2 = analogRead(FLEX_PIN2);
  float val2 = map(flexADC2, 744, 899, 18, 0);

  int flexADC3 = analogRead(FLEX_PIN3);
  float val3 = map(flexADC3, 667, 878, 18, 0);

  int flexADC4 = analogRead(FLEX_PIN4);
  float val4 = map(flexADC4, 578, 792, 18, 0);

  Serial.println();
  Serial.println(val1);
  Serial.println(val2);
  Serial.println(val3);
  Serial.println(val4);
  //forwards
  if (val1 > 1 && val2 <= 1 && val3<=1 && val4<=1){
    digitalWrite(in1, HIGH);
    digitalWrite(in2, LOW);
    // set speed to 200 out of possible range 0~255
    analogWrite(enA, 200);
    // turn on motor B
    digitalWrite(in3, HIGH);
    digitalWrite(in4, LOW);
    analogWrite(enB, 200);
    delay(2000);
  }
  //backwards
  if (val2>1 && val1 <=1 && val3<=1 && val4 <=1){

    digitalWrite(in1, LOW);
    digitalWrite(in2, HIGH);
    digitalWrite(in3, LOW);
    digitalWrite(in4, HIGH);
    delay(2000);
  }
  //off
  if (val1 <=1 && val2 <=1 && val3 <=1 && val4 <=1){
    digitalWrite(in1, LOW);
    digitalWrite(in2, LOW);
    digitalWrite(in3, LOW);
    digitalWrite(in4, LOW);
  }
  //right
  if (val3>1 && val1 <=1 && val2 <=1 && val4 <=1) {
    digitalWrite(in1, LOW);
    digitalWrite(in2, HIGH);
    digitalWrite(in3, LOW);
    digitalWrite(in4, LOW);
  }
  //left
  if (val4>1 && val1 <=1 && val2 <=1 && val3 <=1 ){
    digitalWrite(in1, LOW);
    digitalWrite(in2, LOW);
  }
}

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    digitalWrite(in3, HIGH);
    digitalWrite(in4, LOW);
}
if (val1 > 1 && val2 > 1 && val3 <=1 && val4 <=1){
    servoVal = val1*15;
    one.write(servoVal);
}
}

void loop()
{
    main1();
}
```