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#include <AFMotor.h>
AF_DCMotor motor1(1);
AF_DCMotor motor2(2);
AF_DCMotor motor3(3);
AF_DCMotor motor4(4);

const int trigPin = 9;
const int echoPin = 10;
const int trigPin1 = 1;

const int echoPin1 = 2;
const int trigPin2 = 8;
const int echoPin2 = 13;
// defines variables
long duration;
int distance;
long duration1;
int distance1;
long duration2;
int distance2;
long duration3;
int distance3;

void setup() {

pinMode(trigPin, OUTPUT); // Sets the trigPin as an Output
pinMode(echoPin, INPUT); // Sets the echoPin as an Input
/*pinMode(trigPin1, OUTPUT); // Sets the trigPin as an Output
pinMode(echoPin1, INPUT);
// Sets the echoPin as an Input
pinMode(trigPin2, OUTPUT); // Sets the trigPin as an Output
pinMode(echoPin2, INPUT);// Sets the echoPin as an Input */
Serial.begin(9600); // Starts the serial communication

motor1.setSpeed(255);
motor2.setSpeed(255);
motor3.setSpeed(255);
motor4.setSpeed(255);
motor1.run(FORWARD);
motor2.run(FORWARD);
motor3.run(FORWARD);
motor4.run(FORWARD);

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}
void loop() {
// Clears the trigPin
digitalWrite(trigPin, LOW);

delayMicroseconds(2);
// Sets the trigPin on HIGH state for 10 micro seconds
digitalWrite(trigPin, HIGH);
delayMicroseconds(10);
digitalWrite(trigPin, LOW);
// Reads the echoPin, returns the sound wave travel time in microseconds
duration = pulseIn(echoPin, HIGH);
// Calculating the distance
distance= duration*0.034/2;

// Prints the distance on the Serial Monitor
Serial.print("Distance: ");
Serial.println(distance);

if(distance <30 && distance >1 ){
  motor1.run(RELEASE);
  motor2.run(RELEASE);
  motor3.run(RELEASE);
  motor4.run(RELEASE);

  // Clears the trigPin
  digitalWrite(trigPin, LOW);

  delayMicroseconds(2);
  // Sets the trigPin on HIGH state for 10 micro seconds
  digitalWrite(trigPin1, HIGH);
  delayMicroseconds(10);
  digitalWrite(trigPin1, LOW);
  // Reads the echoPin, returns the sound wave travel time in microseconds
  duration1 = pulseIn(echoPin1, HIGH);
  // Calculating the distance
  distance1= duration1*0.034/2;

  // Prints the distance on the Serial Monitor
  Serial.print("Distance1: ");
  Serial.println(distance1);
}
}

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delay(50);

// Clears the trigPin
digitalWrite(trigPin2, LOW);

delayMicroseconds(2);
// Sets the trigPin on HIGH state for 10 micro seconds
digitalWrite(trigPin2, HIGH);
delayMicroseconds(10);
digitalWrite(trigPin2, LOW);
// Reads the echoPin, returns the sound wave travel time in microseconds
duration2 = pulseIn(echoPin2, HIGH);
// Calculating the distance
distance2= duration2*0.034/2;

// Prints the distance on the Serial Monitor
Serial.print("Distance2: ");

Serial.println(distance2);

    if(distance2 > distance1){
    motor1.run(BACKWARD);
    motor2.run(BACKWARD);
    motor3.run(FORWARD);
    motor4.run(FORWARD);
    delay(500);
    }
    if(distance1 > distance2){
    motor1.run(FORWARD);
    motor2.run(FORWARD);
    motor3.run(BACKWARD);
    motor4.run(BACKWARD);
    delay(500);
    }
}

else{
    motor1.run(FORWARD);
    motor2.run(FORWARD);
    motor3.run(FORWARD);
    motor4.run(FORWARD);
}
}

```

}