



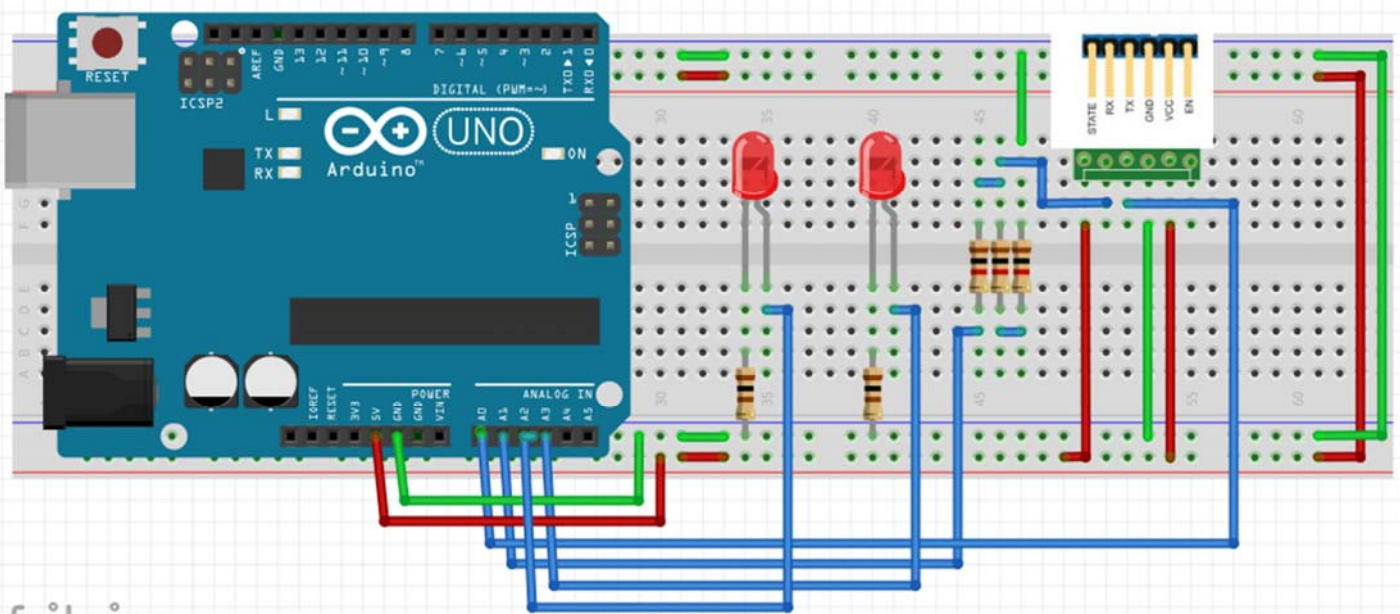
Lecture (09) connecting Motor shield and BT module

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II



```

#include <SoftwareSerial.h> //Software Serial
Port
#define RxD A0
#define TxD A1

#define led01 A2
#define led02 A3
SoftwareSerial blueToothSerial(RxD,TxD);
int led01_status=0;
int led02_status=0;
void setup()
{
  Serial.begin(9600);
  pinMode(RxD, INPUT);
  pinMode(TxD, OUTPUT);
  pinMode(led01, OUTPUT);
  pinMode(led02, OUTPUT);
  digitalWrite(led01,led01_status);
  digitalWrite(led02,led02_status);

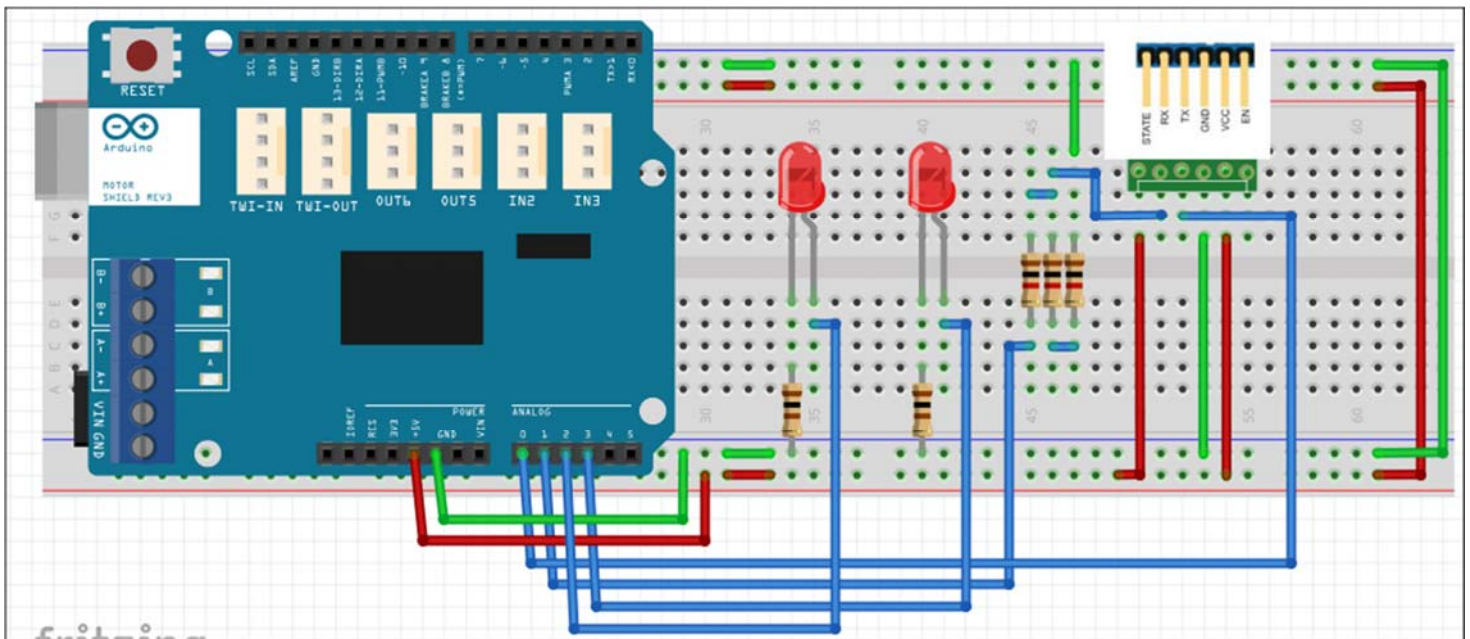
  Serial.println("*****
*****");
  Serial.println("* welcome to BT remote
control *");

```

```

Serial.println("*****
*****");
  blueToothSerial.flush();
}
void loop()
{
  char data = 0;
  if(blueToothSerial.available() > 0)
  {
    data = blueToothSerial.read();
    Serial.print("Recived : ");
    Serial.print(data);
    Serial.print("\n\r");
    if(data == '1')
    {
      led01_status=!led01_status;
      digitalWrite(led01,led01_status);
    }
    else if(data == '2')
    {
      led02_status=!led02_status;
      digitalWrite(led02,led02_status);
    }
  }
}
}

```




```

#include <SoftwareSerial.h> //Software Serial
Port
#include "DCM.cpp"
#define RxD A0
#define TxD A1
#define motor1 11
#define motor2 3
SoftwareSerial blueToothSerial(RxD,TxD);

void setup()
{
  Serial.begin(9600);
  pinMode(RxD, INPUT);
  pinMode(TxD, OUTPUT);

  blueToothSerial.begin(9600);
  blueToothSerial.flush();
}
void loop()
{
  char data = 0;
  if(blueToothSerial.available() > 0) {
    data = blueToothSerial.read();

```

```

Serial.print("Recived : ");
Serial.print(data); //Print Value inside
data in Serial monitor
Serial.print("\n\r"); //New line
if(data == '1') // 48 forward
{
  motor(1, FORWARD, 128);
  motor(2, FORWARD, 128);
  delay(100);
  motor(1, RELEASE, 0);
  motor(2, RELEASE, 0);
}
else if(data == '2') // 49 //back
{
  motor(1, BACKWARD, 128);
  motor(2, BACKWARD, 128);
  delay(100);
  motor(1, RELEASE, 0);
  motor(2, RELEASE, 0);
}
}
}
}

```

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Thanks,..
See you next week (ISA),...

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