```
#include <Servo.h>    //?????
#include <DistanceSRF04.h>
DistanceSRF04 Dist;
int distance;
int EN2 = 2;
int EN3 = 3;
int EN4 = 4;
int EN5 = 5;
int LED1 = 6;
int LED2 = 7;
int val,kkl,lkf;
int lx=90;
//2???
Servo servoX; //??X??? ??
Servo servoY; //??Y??? ??
int mkk;
////////////////////////////////////
void ting(void)
      {
        digitalWrite(EN2,LOW);
        digitalWrite(EN3,LOW);
        digitalWrite(EN4,LOW);
        digitalWrite(EN5,LOW);
      }

void qian(void)
      {
        digitalWrite(EN2,LOW);
        digitalWrite(EN3,HIGH);
        digitalWrite(EN4,LOW);
        digitalWrite(EN5,HIGH);
      }
void hou(void)
      {
        digitalWrite(EN2,HIGH);
        digitalWrite(EN3,LOW);
        digitalWrite(EN4,HIGH);
        digitalWrite(EN5,LOW);
      }
void zuo(void)
      {
        digitalWrite(EN2,LOW);
        digitalWrite(EN3,HIGH);
        digitalWrite(EN4,HIGH);
        digitalWrite(EN5,LOW);
      }
void you(void)
      {
        digitalWrite(EN2,HIGH);
```

```
        digitalWrite(EN3,LOW);
        digitalWrite(EN4,LOW);
        digitalWrite(EN5,HIGH);

      }
//????
void servo_left()
{
 int servotemp=servoX.read();//??????????
 servotemp-=2;//????1?
 if(servotemp<170&&servotemp>10) //???????????10??170?
 servoX.write(servotemp);
 else if (servotemp<=10)  servoX.write(10);
 else servoX.write(170);
}


//????
void servo_right()
{
 int servotemp=servoX.read();//??????????
 servotemp+=2;//????1?
 if(servotemp<170&&servotemp>10)//???????????10??170?
 servoX.write(servotemp);
 else if (servotemp<=10)  servoX.write(10);
 else servoX.write(170);
}


//????
void servo_up()
{
 int servotemp1=servoY.read();//??????????
 servotemp1+=2;//????1?
 if(servotemp1<170&&servotemp1>10)//???????????10??170?
 servoY.write(servotemp1);
 else if (servotemp1<=10)  servoY.write(10);
 else servoY.write(170);
}


//????
void servo_down()
{
 int servotemp1=servoY.read();//??????????
 servotemp1-=2;//????1?
 if(servotemp1<170&&servotemp1>10)//???????????10??170?
 servoY.write(servotemp1);
 else if (servotemp1<=10)  servoY.write(10);
 else servoY.write(170);
```

```
}
void setup()
{
 Dist.begin(8,9);
 servoX.attach(10);//?????10?
 servoY.attach(11);//?????11?
 servoX.write(90);//?????????90?
 servoY.write(90);//?????????90?
 Serial.begin(9600);//??????9600bps
 pinMode(EN2,OUTPUT);
 pinMode(EN3,OUTPUT);
 pinMode(EN4,OUTPUT);
 pinMode(EN5,OUTPUT);
 pinMode(LED1,OUTPUT);
 pinMode(LED2,OUTPUT);
  for(kkl=0;kkl<60;kkl++)
 {
   digitalWrite(LED1,HIGH);
   digitalWrite(LED2,HIGH);
   delay(500);//??500M????WF171???????????????
   digitalWrite(LED1,LOW);
   digitalWrite(LED2,LOW);
   delay(500);
 }
 lkf=0;
}


void loop()
{
 distance = Dist.getDistanceCentimeter();
 if(distance<=5 & distance>1)
 {
   hou();
   delay(100);
   ting();
   distance=0;
 }
 if(Serial.available())
 {
   lkf = Serial.read();
 switch(lkf)
 {
 case 'a':
    qian();
    break;
    lkf=0;
  case 'b':
    hou();
    lkf=0;
```

```
    break;
   case 'c':
    zuo();
    lkf=0;
    break;
   case 'd':
   you();
   lkf=0;
    break;
   case 'e':
   ting();
   lkf=0;
    break;
   case 'j':
    servo_left();
    lkf=0;
    break;
   case 'l':
    servo_right();
    lkf=0;
    break;
   case 'k':
   servo_up();
   lkf=0;
   break;
   case 'i':
    servo_down();
    lkf=0;
    break;
  case 'n':
    digitalWrite(LED1,HIGH);
    digitalWrite(LED2,HIGH);
    lkf=0;
    break;
  case 'm':
   digitalWrite(LED1,LOW);
   digitalWrite(LED2,LOW);
   lkf=0;
   break;
}
}
}
```