

```

#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);

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    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);
}

```

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}
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;
}

```

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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;
    }
  }
}

```

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    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;
}
}
}
```