

```
// ΟΜΑΔΑ STEAM ΓΥΜΝΑΣΙΟΥ ΝΕΑΠΟΛΗΣ ΛΑΣΙΘΙΟΥ
```

```
#include<SoftwareSerial.h>
```

```
#include <Servo.h>
```

```
Servo myservo; // create servo object to control a servo
```

```
Servo myservo2; // create servo object to control a servo
```

```
SoftwareSerial MyBlue(10, 11); // RX | TX
```

```
char val;
```

```
void setup() {
```

```
  Serial.begin(9600);
```

```
  MyBlue.begin(9600);
```

```
}
```

```
void loop() {
```

```
  if (MyBlue.available())
```

```
  {
```

```
    val = MyBlue.read(); // read bluetooth values
```

```
    delay(150);
```

```
    if (val=='B')
```

```
    {
```

```
      Serial.println("Backwards");
```

```
      myservo.attach(3);
```

```
      myservo.write(110); // turn servo clockwise value > 90
```

```
      delay(220);
```

```
      myservo.detach(); // stop servo
```

```
    }
```

```
    if (val=='F')
```

```
    {
```

```
      Serial.println("Forward");
```

```
      myservo.attach(3);
```

```
      myservo.write(80); // turn servo counterclockwise value < 90
```

```
      delay(180);
```

```
      myservo.detach();
```

```
    }
```

```
    if (val=='R')
```

```
    {
```

```
      Serial.println("Right");
```

```
      myservo2.attach(5);
```

```
      myservo2.write(80);
```

```
      delay(150);
```

```
      myservo2.detach();
```

```
    }
```

```
    if (val=='L')
```

```
    {
```

```
Serial.println("Left");
myservo2.attach(5);
myservo2.write(110);
delay(150);
myservo2.detach();
}
Serial.println("***");
Serial.println(val);
Serial.println("***");
val = MyBlue.read();
}
delay(100);
}
```