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\*Pat's IR Robot- Keep finger on button for movement, off to stop.

\*19/9/2018

\*A049-Crazy 2WD Buggy-Infrared

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#include <IRremote.h>

// connect motor controller pins to Arduino digital pins

// motor one`

const int in1 = 9;

const int in2 = 5;

// motor two

const int in3 = A5;

const int in4 = 6;

// LEDs

const int ledBlue = 4;

const int ledWhite = 5;

const int delayTime=1000;

const int RECV\_PIN = 2;

IRrecv irrecv(RECV\_PIN);

void setup()

{

 // set all the motor control pins to outputs

 pinMode(in1, OUTPUT);

 pinMode(in2, OUTPUT);

 pinMode(in3, OUTPUT);

 pinMode(in4, OUTPUT);

 pinMode(ledBlue, OUTPUT);

 pinMode(ledWhite, OUTPUT);

 irrecv.enableIRIn(); // Start the receiver

}

void loop()

{

 // turn on motor A

 digitalWrite(in1, HIGH);

 digitalWrite(in2, LOW);

 digitalWrite(ledBlue, HIGH);

// turn on motor B

 digitalWrite(in3, HIGH);

 digitalWrite(in4, LOW);

 digitalWrite(ledBlue, HIGH);

 delay(delayTime);

//}

//void backwards()

//{

// turn on motor A

 digitalWrite(in1, LOW);

 digitalWrite(in2, HIGH);

 digitalWrite(ledWhite, HIGH);

 // turn on motor B

 digitalWrite(in3, LOW);

 digitalWrite(in4, HIGH);

 digitalWrite(ledWhite, HIGH);

 delay(delayTime);

//}

//void right()

//{

 // turn on motor A

 digitalWrite(in1, HIGH);

 digitalWrite(in2, LOW);

 // turn on motor B

 digitalWrite(in3, LOW);

 digitalWrite(in4, LOW);

 delay(delayTime);

//}

//void left()

//{

 // turn on motor A

 digitalWrite(in1, LOW);

 digitalWrite(in2, LOW);

 // turn on motor B

 digitalWrite(in3, HIGH);

 digitalWrite(in4, LOW);

 delay(delayTime);

}