

# LAMPIRAN

## LAMPIRAN *SCRIPT PROGRAM ROUV*

```
#include <Servo.h>

const int joyx = A0;
const int joyy = A1;
const int bacaMode = 16;
const int bacaPump = A3;

int bacaX, bacaY;
int valX = 90;
int valY = 90;
byte mode = 1;
byte modepin = 0;
byte reading;
byte previous = HIGH;
Servo servoX;
Servo servoY;

void setup(){
  pinMode(A0,INPUT);    //pin joystick X
  pinMode(A1,INPUT);    //pin joystick Y
  pinMode(A2,INPUT);    //pin baca Mode
  pinMode(A3,INPUT);    //pin baca pompa
  pinMode(A4,INPUT);    //pin tangan cengkram

  pinMode(12,OUTPUT);   //pin pompa
  pinMode(19,OUTPUT);   //pin lampu

  //pin-pin motor baling-baling
  pinMode(0,OUTPUT);
  pinMode(1,OUTPUT);
  pinMode(8,OUTPUT);
  pinMode(13,OUTPUT);

  //pin lampu mode
  pinMode(2,OUTPUT);    //mode baling-baling
  pinMode(4,OUTPUT);    //mode camera
  pinMode(7,OUTPUT);    //mode tangan robot

  servoX.attach(3);
  servoY.attach(5);
  servoX.write(90);
  servoY.write(90);
}
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void motorHenti(){
  digitalWrite(1,LOW);
  digitalWrite(8,LOW);
  digitalWrite(0,LOW);
  digitalWrite(13,LOW);
}

void motorMaju(){
  digitalWrite(1,HIGH);
  digitalWrite(8,LOW);
  digitalWrite(0,LOW);
  digitalWrite(13,HIGH);
}

void motorMundur(){
  digitalWrite(1,LOW);
  digitalWrite(8,HIGH);
  digitalWrite(0,HIGH);
  digitalWrite(13,LOW);
}

void motorKiri(){
  digitalWrite(1,LOW);
  digitalWrite(8,HIGH);
  digitalWrite(0,LOW);
  digitalWrite(13,HIGH);
}

void motorKanan(){
  digitalWrite(1,HIGH);
  digitalWrite(8,LOW);
  digitalWrite(0,HIGH);
  digitalWrite(13,LOW);
}

void loop(){
  bacaX = analogRead(joyx);
  bacaY = analogRead(joyy);
  reading = digitalRead(bacaMode);

  if(mode == 1){
    digitalWrite(2,HIGH);
    digitalWrite(4,LOW);
    digitalWrite(7,LOW);
    if(bacaX >=750){

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    motorKiri();
}
if(bacaY >=750){
    motorMundur();
}
if(bacaX <=300){
    motorKanan();
}
if(bacaY <=300){
    motorMaju();
}
if((bacaX > 300) && (bacaX <750) && (bacaY > 300) && (bacaY <750)) {
    motorHenti();
}
delay(10);
}
else if(mode == 2){
    digitalWrite(2,LOW);
    digitalWrite(4,HIGH);
    digitalWrite(7,LOW);
    motorHenti();
    if(bacaX >750){
        valX = valX+2;
        if(valX > 1000){
            valX = 1000;
        }
        delay(10);
    }
    if(bacaX < 300){
        valX = valX-2;
        if(valX <= 10){
            valX = 10;
        }
        delay(10);
    }
    if(bacaY >750){
        valY = valY+2;
        if(valY > 1000){
            valY = 1000;
        }
        delay(10);
    }
    if(bacaY < 300){
        valY = valY-2;
        if(valY <= 10){
            valY = 10;
        }
    }
}

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    }
    delay(10);
  }
  servoX.write(valX);
  servoY.write(valY);
  delay(20);
}
else if(mode == 3){
  digitalWrite(2,LOW);
  digitalWrite(4,LOW);
  digitalWrite(7,HIGH);
};

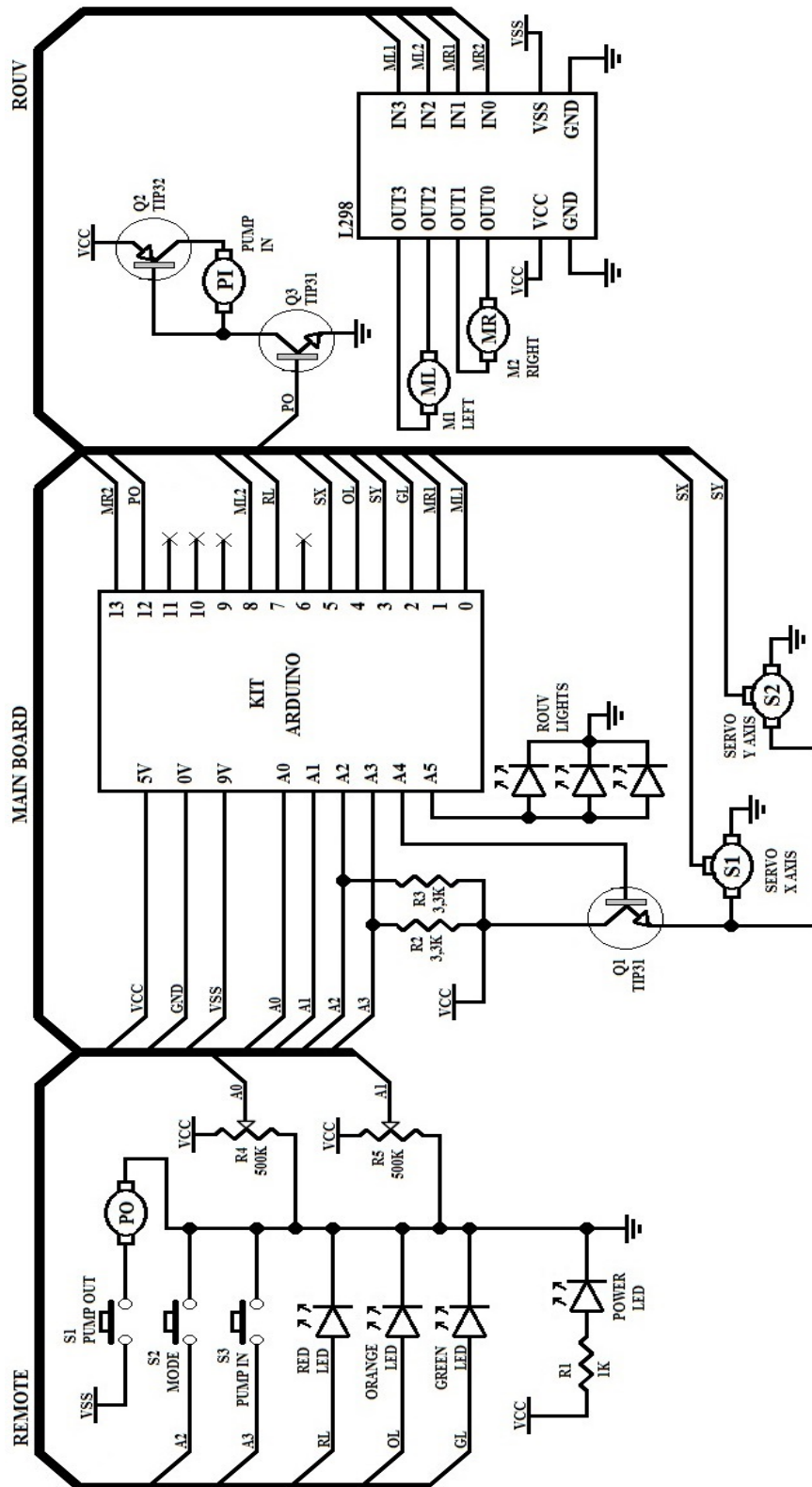
if((reading == LOW) && (previous == HIGH)){
  mode++;
  modepin=0;
  if(mode > 3){
    mode =1;
  }
  delay(20);
}
previous = reading;

if(bacaPump <20) {
  digitalWrite(12,HIGH);
}

if(bacaPump >1000){
  digitalWrite(12,LOW);
}
delay(20);
}

```

# LAMPIRAN SKEMA RANGKAIAN ROUV



# LAMPIRAN SKEMA KITARDUINO SEVERINO

