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#include <Servo.h>

Servo myservoL;
Servo myservoR;

#define echoPin 10 // attach pin D2 Arduino to pin Echo of HC-SR04
#define trigPin 9 //attach pin D3 Arduino to pin Trig of HC-SR04
long duration; // variable for the duration of sound wave travel
int distance; // variable for the distance measurement

void setup()
{
  myservoL.attach(3);
  myservoR.attach(2);
  pinMode(trigPin, OUTPUT); // Sets the trigPin as an OUTPUT
  pinMode(echoPin, INPUT); // Sets the echoPin as an INPUT
  Serial.begin(115200); // // Serial Communication is starting with 9600 of
baudrate speed
}

void loop() {

  digitalWrite(trigPin, LOW);
  delayMicroseconds(2);
  // Sets the trigPin HIGH (ACTIVE) for 10 microseconds
  digitalWrite(trigPin, HIGH);
  delayMicroseconds(10);
  digitalWrite(trigPin, LOW);
  // Reads the echoPin, returns the sound wave travel time in microseconds
  duration = pulseIn(echoPin, HIGH);
  // Calculating the distance
  distance = duration * 0.034 / 2; // Speed of sound wave divided by 2 (go and
back)
  // Displays the distance on the Serial Monitor

  Serial.print(distance);
  Serial.println(" cm");
  delay (50);

  if (distance > 10){

myservoL.write(180); // set servo to mid-point
myservoR.write(0); // set servo to mid-point
}

  if (distance <10 ){

myservoL.write(0); // set servo to mid-point
myservoR.write(0); // set servo to mid-point

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    delay (700); // This delay will change the amount of time your robot will turn.  
    The longer the delay, the further the robot will turn.
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}
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}
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