Program Transmiter

```
const int tombol_maju = A1;

const int tombol_mundur = A0;

const int tombol_kanan = A2;

const int tombol_kiri = A3;

const int tombol_shift = A4;


int data_maju = 0;

int data_mundur = 0;

int data_kanan = 0;

int data_kiri = 0;

int data_shift = 0;


void setup() {

 Serial.begin(9600);

 pinMode(tombol_maju,INPUT);

 pinMode(tombol_mundur,INPUT);

 pinMode(tombol_kanan,INPUT);

 pinMode(tombol_kiri,INPUT);

 pinMode(tombol_shift,INPUT);


digitalWrite(tombol_maju,HIGH);

digitalWrite(tombol_mundur,HIGH);

digitalWrite(tombol_kanan,HIGH);

digitalWrite(tombol_kiri,HIGH);

digitalWrite(tombol_shift,HIGH);
```

```
}
void maju()
{
  Serial.println("a");
}
void mundur()
{
  Serial.println("b");
}
void belok_kanan()
{
  Serial.println("c");
}
void belok_kiri()
{
  Serial.println("d");
}
void berhenti()
{
  Serial.println("g");
}
void servo_kanan()
{
  Serial.println("h");
}

void servo_kiri()
```

```arduino
{
  Serial.println("i");
}
void loop() {

  data_maju = digitalRead(tombol_maju);

  data_mundur = digitalRead(tombol_mundur);

  data_kanan = digitalRead(tombol_kanan);

  data_kiri = digitalRead(tombol_kiri);

  data_shift = digitalRead(tombol_shift);


  if(data_maju == LOW && data_shift == HIGH){

    maju();

  }
  if(data_mundur == LOW && data_shift == HIGH){

    mundur();

  }
  if(data_kanan == LOW && data_shift == HIGH){

    belok_kanan();

  }
  if(data_kiri == LOW && data_shift ==HIGH){

    belok_kiri();

  }
  if(data_shift == LOW && data_kiri == HIGH && data_kanan == HIGH && data_maju == HIGH && data_mundur == HIGH ){

    berhenti();

  }
```

```
if(data_shift == LOW && data_maju == LOW){

  servo_kanan();

}

if(data_shift == LOW && data_mundur == LOW){

  servo_kiri();

}

}
```

Program Receiver

```
 #include<SoftwareSerial.h>

 #include<Servo.h>


char inByte;

const int kanan_maju = 3;

const int kanan_mundur = 4;

const int kecepatan_kanan = 5;

const int kecepatan_kiri = 6;

const int kiri_maju = A5;

const int kiri_mundur = A4;


int sudut;

 Servo kamera;

void mundur()

{

digitalWrite(kanan_maju,HIGH);

digitalWrite(kanan_mundur,LOW);

analogWrite(kecepatan_kanan,255);

analogWrite(kecepatan_kiri,255);
```

```
digitalWrite(kiri_maju,HIGH);

digitalWrite(kiri_mundur,LOW);

}

void maju()

{

digitalWrite(kanan_maju,LOW);

digitalWrite(kanan_mundur,HIGH);

analogWrite(kecepatan_kanan,255);

analogWrite(kecepatan_kiri,255);

digitalWrite(kiri_maju,LOW);

digitalWrite(kiri_mundur,HIGH);

}

void belok_kanan()

{

digitalWrite(kanan_maju,LOW);

digitalWrite(kanan_mundur,HIGH);

analogWrite(kecepatan_kanan,128);

analogWrite(kecepatan_kiri,255);

digitalWrite(kiri_maju,HIGH);

digitalWrite(kiri_mundur,LOW);

}

void belok_kiri()

{

digitalWrite(kanan_maju,HIGH);

digitalWrite(kanan_mundur,LOW);

analogWrite(kecepatan_kanan,255);

analogWrite(kecepatan_kiri,128);
```

```
digitalWrite(kiri_maju,LOW);

digitalWrite(kiri_mundur,HIGH);

}

void berhenti ()

{

digitalWrite(kanan_maju,LOW);

digitalWrite(kanan_mundur,LOW);

analogWrite(kecepatan_kanan,0);

analogWrite(kecepatan_kiri,0);

digitalWrite(kiri_maju,LOW);

digitalWrite(kiri_mundur,LOW);


}

void servo_kanan()

{

  sudut = sudut+15;

  if(sudut>=179){sudut=179;}

  kamera.write(sudut);

  delay(500);

  inByte==0;

}


void servo_kiri()

{

  sudut = sudut-15;

  if(sudut<=1){sudut=1;}

 kamera.write(sudut);
```

```
  inByte==0;

 delay(500);

 }


void  setup()

{

pinMode(kanan_maju,OUTPUT);

 pinMode(kanan_mundur,OUTPUT);

 pinMode(kecepatan_kanan,OUTPUT);

 pinMode(kecepatan_kiri,OUTPUT);

 pinMode(kiri_maju,OUTPUT);

 pinMode(kiri_mundur,OUTPUT);


 Serial.begin(9600);

kamera.attach(2);

}

void loop()

{


if (Serial.available()>0){

inByte = Serial.read ();

Serial.println(inByte);


if(inByte=='a'){

 Serial.println("maju");

 maju();

}
```

```
if(inByte=='b'){

  Serial.println("mundur");

  mundur();

}


if(inByte=='c'){

  Serial.println("belok_kanan");

  belok_kanan();

}

if(inByte=='d'){

  Serial.println("belok_kiri");

  belok_kiri();

}

if(inByte=='g'){

  Serial.println("berhenti");

  berhenti();

}

if(inByte=='h'){

  Serial.println("servo_kanan");

  servo_kanan();

}

if(inByte=='i'){

  Serial.println("servo_kiri");

  servo_kiri();

}

}

}
```