#include <SoftwareSerial.h>

#include <Wire.h> //SoftwareSerialWire SoftwareSerial

#include <Servo.h>

SoftwareSerial I2CBT(A0,A1); //PIN10PIN11RXTX

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

int pos = 0; // variable to store the servo position

int INA = 9;

int INB = 10;

//int LED = 13;

void setup() {

 Serial.begin(9600); //Arduino9600

 I2CBT.begin(9600); //57600

 myservo.attach(3); // attaches the servo on pin 3 to the servo object

 pinMode(INA,OUTPUT);

 pinMode(INB,OUTPUT);

}

void loop() {

 byte cmmd[20];

 int insize;

 servo(90);

 while(1){

 if ((insize=(I2CBT.available()))>0){

 Serial.print("input size = ");

 Serial.println(insize); //

 for (int i=0; i<insize; i++) {

 Serial.print(cmmd[i]=char(I2CBT.read()));//

 //Serial.print("\n");

 } //for

 switch (cmmd[0]) {

 case 97: //'a'

 //digitalWrite(LED,HIGH);

 motorforward();

 Serial.print(" go");

 break;

 case 98: //'b'

 //digitalWrite(LED,LOW);

 motorstop();

 Serial.print(" stop");

 break;

 case 102: //'f'

 //digitalWrite(LED,LOW);

 motorback();

 Serial.print(" back");

 break;

 case 99: //'c'

 servo(150);

 Serial.print(" Left");

 break;

 case 100: //'d'

 servo(90);

 Serial.print(" Ctr");

 break;

 case 101: //'e'

 servo(30);

 Serial.print(" Right");

 break;

 } //Switch

 Serial.print("\n");

 } //if

 } //while

}

//\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*

void servo(int servopos) {

 myservo.write(servopos); // tell servo to go to position in variable 'pos'

 delay(15); // waits 15ms for the servo to reach the position

}

void motorforward() {

 digitalWrite(INA,LOW);

 digitalWrite(INB,HIGH);

 //delay(1000);

}

void motorstop() {

 digitalWrite(INA,LOW);

 digitalWrite(INB,LOW);

 //delay(1000);

}

void motorback() {

 digitalWrite(INA,HIGH);

 digitalWrite(INB,LOW);

 //delay(1000);

}