#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);

}