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// ΟΜΑΔΑ STEAM ΓΥΜΝΑΣΙΟΥ ΝΕΑΠΟΛΗΣ ΛΑΣΙΘΙΟΥ
#include<SoftwareSerial.h>
#include <Servo.h>

Servo myservo;
SoftwareSerial MyBlue(10, 11); // RX | TX

int motor1pin1 = 4;
int motor1pin2 = 5;
int speedpin=6;
char val;
long mspeed=0;


void setup()
{
  // put your setup code here, to run once:
 pinMode(motor1pin1, OUTPUT);
 pinMode(motor1pin2, OUTPUT);
 pinMode(speedpin, OUTPUT);

 myservo.attach(3);
 Serial.begin(9600);
 MyBlue.begin(9600);
}


void loop()
{
 if (MyBlue.available())
   {
   Serial.println("***");
    val = MyBlue.read();
   Serial.println("***");
   Serial.println(val);
   Serial.println("***");


    if (val=='L')
    {
    Serial.println("left");
    myservo.write(140);
    }
   if (val=='R')
    {
    Serial.println("right");
    myservo.write(40);
    }
   if (val=='F')
```

```
   {
   Serial.println("forward");
    if (mspeed <= 245)
    {
      if (mspeed<0)
     {
       mspeed=mspeed+10;
       //Controlling speed (0 = off and 255 = max speed):
      analogWrite(speedpin, abs(mspeed)); //ENA pin
       // put your main   code here, to run repeatedly:
      digitalWrite(motor1pin1, LOW);
      digitalWrite(motor1pin2,HIGH);
     }else
     {
       mspeed=mspeed+10;
       //Controlling speed (0 = off and 255 = max speed):
      analogWrite(speedpin, abs(mspeed)); //ENA pin
      digitalWrite(motor1pin1, HIGH);
      digitalWrite(motor1pin2, LOW);
     }
    }
   }
   if (val=='B')
   {
   Serial.println("back");
    if (mspeed >= 10)
    {
     mspeed=mspeed-10;
      Serial.println(mspeed);
     //Controlling speed (0 = off and 255 = max speed):
     analogWrite(speedpin, mspeed); //ENA pin
     // put your main   code here, to run repeatedly:
     digitalWrite(motor1pin1, HIGH);
     digitalWrite(motor1pin2, LOW);
    }else
    {
     mspeed=mspeed-10;
     Serial.println(mspeed);
     //Controlling speed (0 = off and 255 = max speed):
     analogWrite(speedpin, abs(mspeed)); //ENA pin
      digitalWrite(motor1pin1, LOW);
     digitalWrite(motor1pin2,HIGH);
     }
    }
   Serial.println(mspeed);
   MyBlue.write(mspeed);
    delay(1000);
  }
}
```