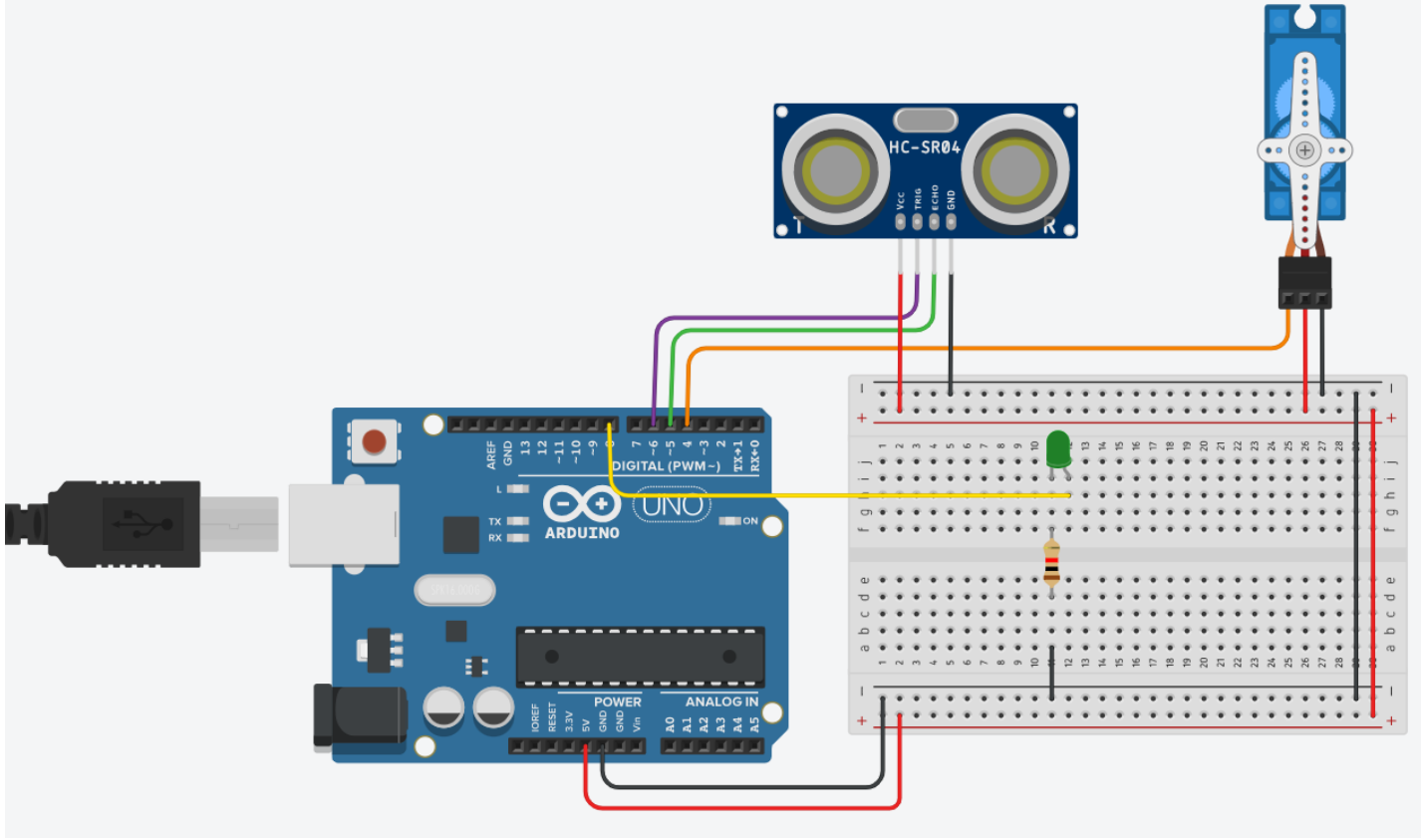INSTITUT
MONTSERRAT

Pràctica-7: Projecte-Barrera-2

```
#include <Servo.h>

Servo servomotor; //variable para controlar el servomotor
int servopin = 4;
int verde = 8;
long cm = 0;
long readUltrasonicDistance(int triggerPin, int echoPin){
pinMode(triggerPin, OUTPUT);
digitalWrite(triggerPin, LOW);

delayMicroseconds(10);
digitalWrite(triggerPin, HIGH);
delayMicroseconds(10);
digitalWrite(triggerPin, LOW);

pinMode(echoPin, INPUT);
return (pulseIn(echoPin, HIGH)*0.01723);
}
void setup(){
servomotor.attach(servopin); //pin 4 conectado a variable
pinMode(verde, OUTPUT);
Serial.begin(9600);
}


void loop(){
cm = (readUltrasonicDistance(6, 5));
if (cm < 100){
servomotor.write(90); //coloca a 90 grados la pluma
digitalWrite(verde, HIGH);
delay(5000);

servomotor.write(0); //regresa a 0 grados
digitalWrite(verde, LOW);
delay(5000);
}

else{
servomotor.write(0);
digitalWrite(verde, LOW);
delay(5000);
}
 }
```

1. Introducció/Objectius:

2. Components/Materials:

3. Anàlisi-funcionament:

4. Anàlisi-Codi:

5. Canvis-realitzats:

6. Experimentacions:

7. Simulació-Tinkercad:

8. Fotos/Videos:

9. Aplicacions:

10. Problemes/Conclusions: