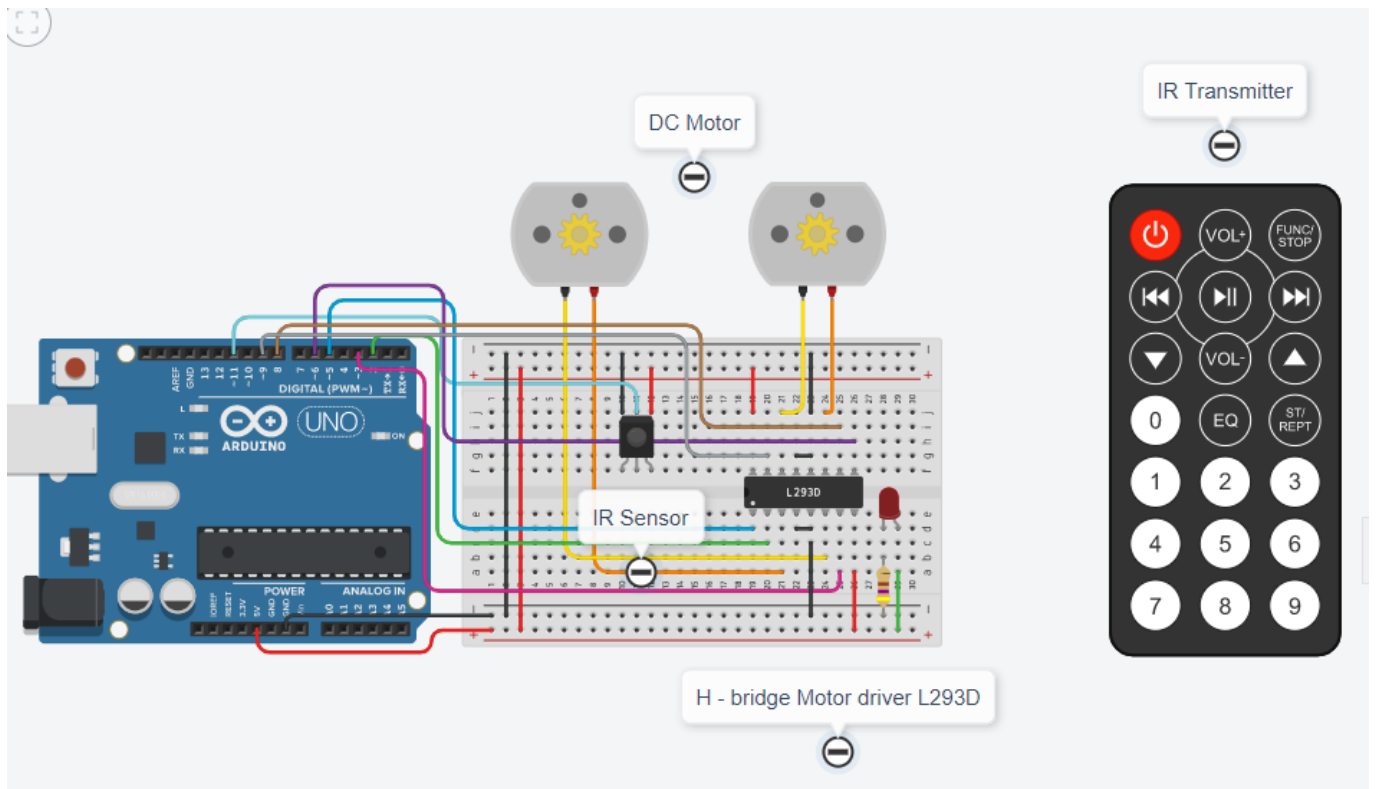


ΕΛΕΓΧΟΣ DC ΚΙΝΗΤΗΡΑ ΜΕ ΤΗΛΕΚΟΝΤΡΟΛ



```

#include <IRremote.h>

IRrecv rc(11);
decode_results results;

const int PWM_M1 = 5;
const int IN1_M1 = 2;
const int IN2_M1 = 3;
const int PWM_M2 = 6;
const int IN1_M2 = 8;
const int IN2_M2 = 9;
int speed = 100;

void setup() {
  Serial.begin(9600);
  rc.enableIRIn();
  pinMode(PWM_M1,OUTPUT);
  pinMode(PWM_M2,OUTPUT);
  pinMode(IN1_M1,OUTPUT);

```

```
pinMode(IN2_M1,OUTPUT);
pinMode(IN1_M2,OUTPUT);
pinMode(IN2_M2,OUTPUT);
}
```

```
void loop() {
  if (rc.decode(&results)) {
    switch(results.value) {
      case 0xFD00FF: //power
        break;
      case 0xFD807F: //vol+
        forward();
        break;
      case 0xFD40BF: //func/stop
        break;
      case 0xFD20DF: //|<<
        turnLeft();
        break;
      case 0xFDA05F: //>||
        stop();
        break ;
      case 0xFD609F: //>>|
        turnRight();
        break ;
      case 0xFD10EF: //down arrow
        speedDown();
        break ;
      case 0xFD906F: //vol-
        backward();
        break ;
      case 0xFD50AF: //up arrow
        speedUp();
        break ;
    }
  }
  rc.resume();
}
```

```
}  
}
```

```
void forward() {  
  Serial.println("forward");  
  analogWrite(PWM_M1, speed);  
  analogWrite(PWM_M2, speed);  
  digitalWrite(IN1_M1, HIGH);  
  digitalWrite(IN2_M1, LOW);  
  digitalWrite(IN1_M2, HIGH);  
  digitalWrite(IN2_M2, LOW);  
}
```

```
void backward() {  
  Serial.println("backward");  
  analogWrite(PWM_M1, speed);  
  analogWrite(PWM_M2, speed);  
  digitalWrite(IN1_M1, LOW);  
  digitalWrite(IN2_M1, HIGH);  
  digitalWrite(IN1_M2, LOW);  
  digitalWrite(IN2_M2, HIGH);  
}
```

```
void turnLeft() {  
  Serial.println("turnLeft");  
  analogWrite(PWM_M1, 0);  
  analogWrite(PWM_M2, speed);  
  digitalWrite(IN1_M1, HIGH);  
  digitalWrite(IN2_M1, LOW);  
  digitalWrite(IN1_M2, HIGH);  
  digitalWrite(IN2_M2, LOW);  
}
```

```
void turnRight() {  
  Serial.println("turnRight");  
  analogWrite(PWM_M1, speed);  
  analogWrite(PWM_M2, 0);  
  digitalWrite(IN1_M1, HIGH);  
  digitalWrite(IN2_M1, LOW);  
  digitalWrite(IN1_M2, HIGH);  
  digitalWrite(IN2_M2, LOW);  
}
```

```
void stop() {  
  Serial.println("stop");  
  digitalWrite(IN1_M1, LOW);  
  digitalWrite(IN2_M1, LOW);  
  
  digitalWrite(IN1_M2, LOW);  
  digitalWrite(IN2_M2, LOW);  
}
```

```
void speedUp() {  
  Serial.println("speedUp");  
  speed+=10;  
  if(speed>255) speed =255;  
  analogWrite(PWM_M1, speed);  
  analogWrite(PWM_M2, speed);  
}
```

```
void speedDown() {  
  Serial.println("speedDown");  
  speed-=10;  
  if(speed<0) speed =0;  
  analogWrite(PWM_M1, speed);  
  analogWrite(PWM_M2, speed);  
}
```