


```

#define M1 11
#define M12 10
#define M2 9
#define M22 5

void setup() {
  // Initialize Arduino pins to outputs
  pinMode(M1, OUTPUT);
  pinMode(M12, OUTPUT);
  pinMode(M2, OUTPUT);
  pinMode(M22, OUTPUT);
}

void loop() {
  goForward();
  delay(3000);

  goBackward();
  delay(3000);

  turnLeft();
  delay(3000);

  turnRight();
  delay(3000);
}

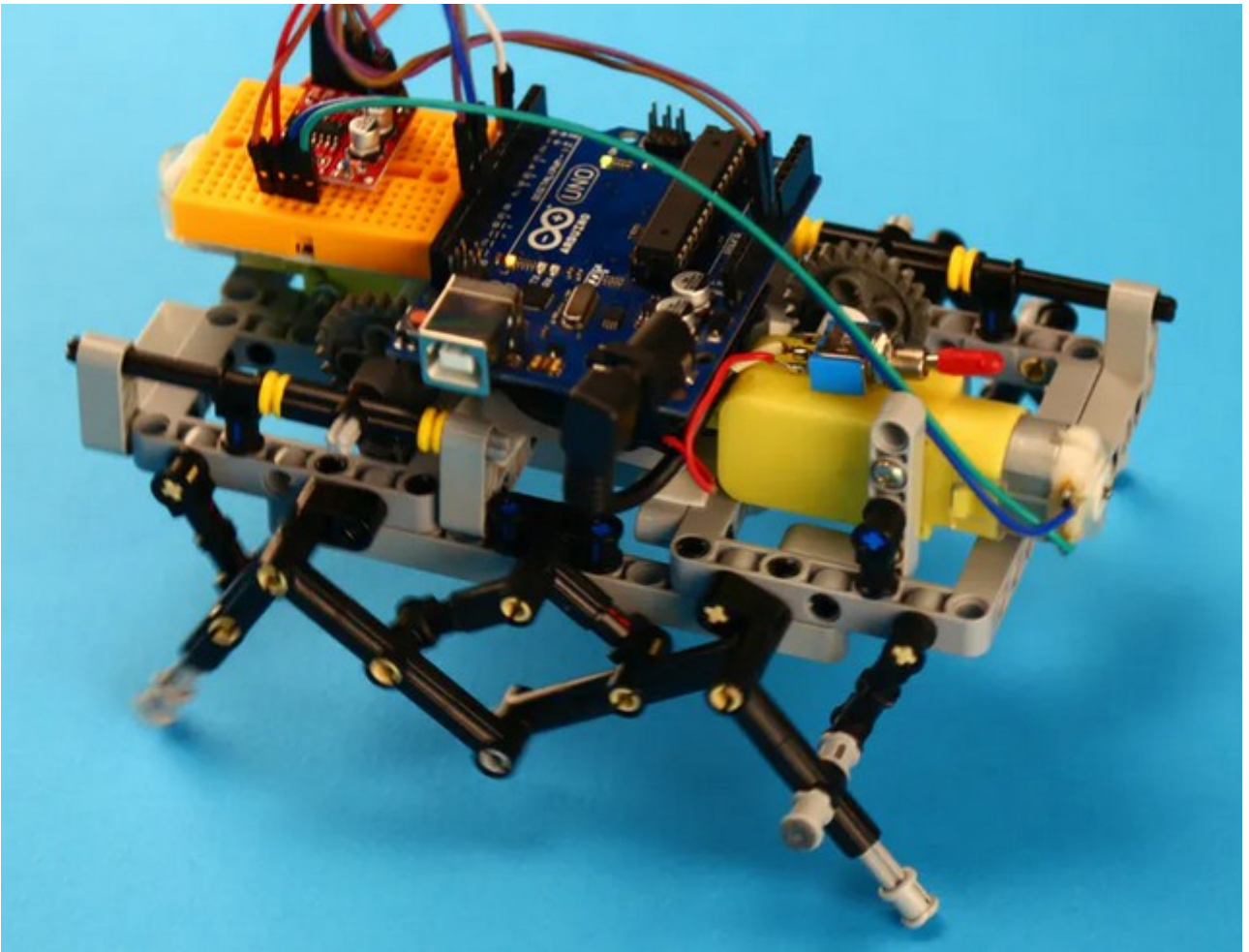
// Configures driver motor pins to go forward.
void goForward() {
  digitalWrite(M1, LOW);
  analogWrite(M12, 200);
  analogWrite(M2, 200);
  digitalWrite(M22, LOW);
}

// Configures driver motor pins to go backward.
void goBackward() {
  digitalWrite(M12, LOW);
  analogWrite(M1, 200);
  analogWrite(M22, 200);
  digitalWrite(M2, LOW);
}

// Configures driver motor pins to turn left.
void turnLeft() {
  digitalWrite(M12, LOW);
  analogWrite(M1, 200);
  analogWrite(M2, 200);
  digitalWrite(M22, LOW);
}

// Configures driver motor pins to turn right.
void turnRight() {
  digitalWrite(M1, LOW);
  analogWrite(M12, 200);
  analogWrite(M22, 200);
  digitalWrite(M2, LOW);
}

```



[Source : Hexapod robot \(Lego style\)](#)