```
import RPi.GPIO as GPIO

from time import sleep


# Suppress warnings

GPIO.setwarnings(False)


# Right Motor

in1 = 17

in2 = 18

en_a = 24  # Corrected GPIO pin number

# Left Motor

in3 = 22

in4 = 23

en_b = 25


# Set up GPIO mode

GPIO.setmode(GPIO.BCM)

GPIO.setup(in1, GPIO.OUT)

GPIO.setup(in2, GPIO.OUT)

GPIO.setup(en_a, GPIO.OUT)


GPIO.setup(in3, GPIO.OUT)

GPIO.setup(in4, GPIO.OUT)

GPIO.setup(en_b, GPIO.OUT)
```

```
# Set up PWM for speed control
q = GPIO.PWM(en_a, 100)  # PWM for right motor
p = GPIO.PWM(en_b, 100)  # PWM for left motor
p.start(75)  # Start PWM with 75% duty cycle
q.start(75)  # Start PWM with 75% duty cycle

# Initialize motors to stop
GPIO.output(in1, GPIO.LOW)
GPIO.output(in2, GPIO.LOW)
GPIO.output(in4, GPIO.LOW)
GPIO.output(in3, GPIO.LOW)

try:
   print("Enter command (w/a/s/d for movement, c to stop):")

   # Infinite loop to read user input
   while True:
      # Get user input
      user_input = input().lower()  # Convert input to lowercase

      if user_input == 'w':
         GPIO.output(in1, GPIO.HIGH)  # Forward for right motor
         GPIO.output(in2, GPIO.LOW)
         GPIO.output(in4, GPIO.HIGH)  # Forward for left motor
         GPIO.output(in3, GPIO.LOW)
```

```
    print("Moving Forward")

elif user_input == 's':
    GPIO.output(in1, GPIO.LOW)   # Backward for right motor
    GPIO.output(in2, GPIO.HIGH)
    GPIO.output(in4, GPIO.LOW)    # Backward for left motor
    GPIO.output(in3, GPIO.HIGH)
    print("Moving Backward")

elif user_input == 'd':
    GPIO.output(in1, GPIO.LOW)    # Right turn
    GPIO.output(in2, GPIO.HIGH)
    GPIO.output(in4, GPIO.LOW)
    GPIO.output(in3, GPIO.LOW)
    print("Turning Right")

elif user_input == 'a':
    GPIO.output(in1, GPIO.HIGH)   # Left turn
    GPIO.output(in2, GPIO.LOW)
    GPIO.output(in4, GPIO.LOW)
    GPIO.output(in3, GPIO.LOW)
    print("Turning Left")

elif user_input == 'c':
    GPIO.output(in1, GPIO.LOW)    # Stop motors
```

```
            GPIO.output(in2, GPIO.LOW)
            GPIO.output(in4, GPIO.LOW)
            GPIO.output(in3, GPIO.LOW)
            print("Stopping Motors")
            break  # Exit the loop to end the script

        else:
            print("Invalid command, please use w/a/s/d for movement or c to stop.")

except KeyboardInterrupt:
    print("\nProgram interrupted by user.")

finally:
    # Cleanup GPIO pins
```