

```
#include <Arduino.h>
```

```
#include <Wire.h>
```

```
#include <SoftwareSerial.h>
```

```
#include <Servo.h>
```

```
double angle_rad = PI/180.0;
```

```
double angle_deg = 180.0/PI;
```

```
double __var__97_305;
```

```
double b;
```

```
float getDistance(int trig,int echo){
```

```
    pinMode(trig,OUTPUT);
```

```
    digitalWrite(trig,LOW);
```

```
    delayMicroseconds(2);
```

```
    digitalWrite(trig,HIGH);
```

```
    delayMicroseconds(10);
```

```
    digitalWrite(trig,LOW);
```

```
    pinMode(echo, INPUT);
```

```
    return pulseIn(echo,HIGH,30000)/58.0;
```

```
}
```

```
Servo servo_9;
```

```
Servo servo_10;
```

```
void setup(){
```

```
    __var__97_305 = getDistance(13,12);
```

```
    b = analogRead(A0+0);
```

```
    pinMode(A0+0,INPUT);
```

```
    servo_9.attach(9); // init pin
```

```
servo_10.attach(10); // init pin
}

void loop(){

  if((__var__97_305) < (5)){
    if((b) > (1000)){
      servo_9.write(180); // write to servo
      servo_10.write(180); // write to servo
    }
  }

  _loop();
}

void _delay(float seconds){
  long endTime = millis() + seconds * 1000;
  while(millis() < endTime)_loop();
}

void _loop(){

}
```