



```

1  /*
2      ROBOT CONTROL SOFTWARE
3      DONI STEFANO - FERRONI ALESSANDRO
4
5      VERSION 1.0
6      LAST UPDATE 08-09-2003
7
8  */
9
10
11 #include <stdlib.h>
12 #include <portb.h>
13 #include <timers.h>
14 #include <delays.h>
15 #include <string.h>
16 #include <pwm.h>
17
18 #include "definitions.h"
19 #include "controller.h"
20 #include "rs232.h"
21 #include "eeeprom.h"
22
23 //version of airboard
24 #define VERSION 1.0
25
26 //Global variables initialization
27
28 char parsingInputBuffer[DIM_SERIAL]
29 //char writeBuffer[DIM_SERIAL]
30 unsigned char dataReady=0, inputDataReady=0
31 int InputData0=0, InputData1=0
32 long total_tick_0=0, total_tick_1=0
33 unsigned char control_counter=0
34 int setpoint_0=0, setpoint_1=0

```

```

1  /*
2      DEFINITIONS.H
3
4      This file contains all global definitions
5  */
6
7  #ifndef __DEFINITIONS_H
8  #define __DEFINITIONS_H
9
10 #include <P18F252.H> // Define PIC we are using
11
12 /*-----
13 ----- DEFINITIONS -----
14 -----*/
15
16 /* define space run (millimeters) per tick. Should
17 be:
18
19 1/500 * 1/M * 2*PI*R
20
21 where:
22
23 500 = steps/motor
24 1/M = motor speed (rpm)
25 2*PI*R = circumference of the wheel

```