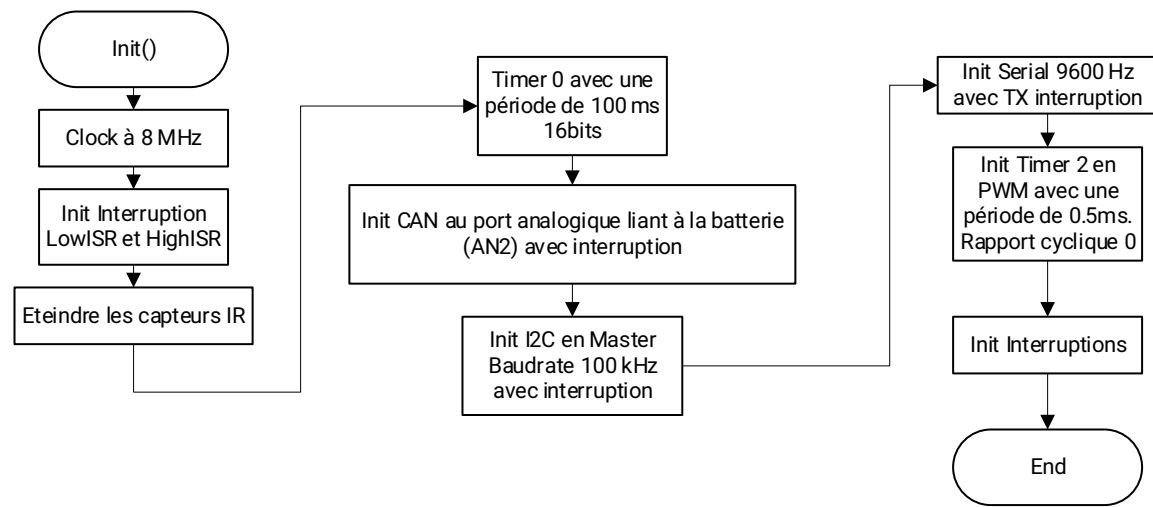
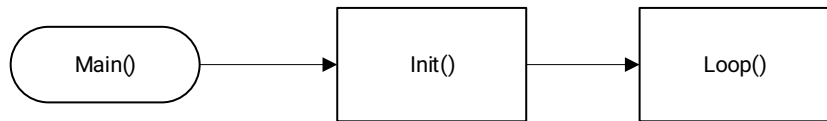


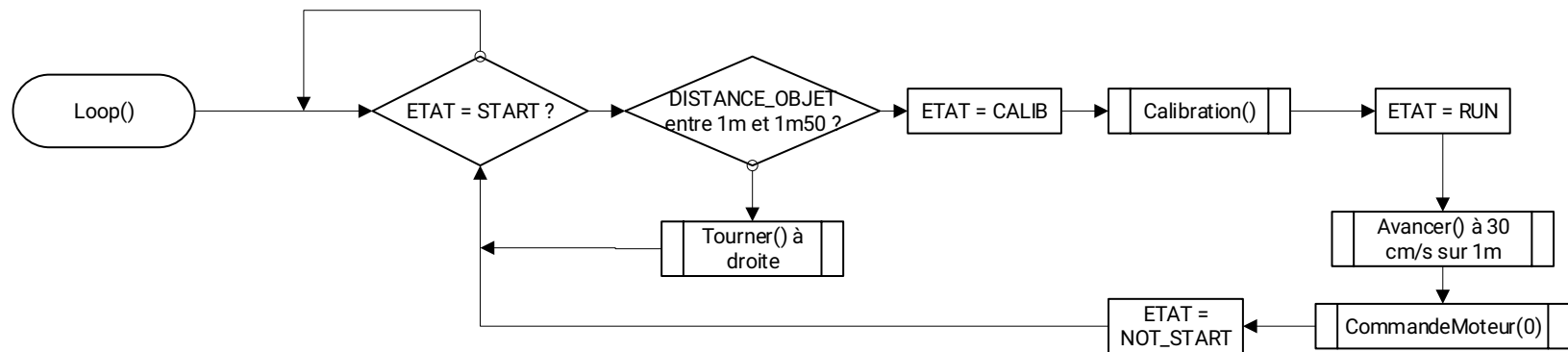
Init



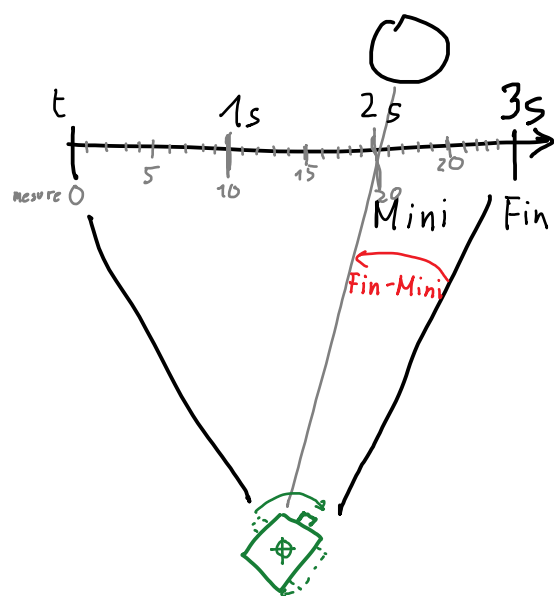
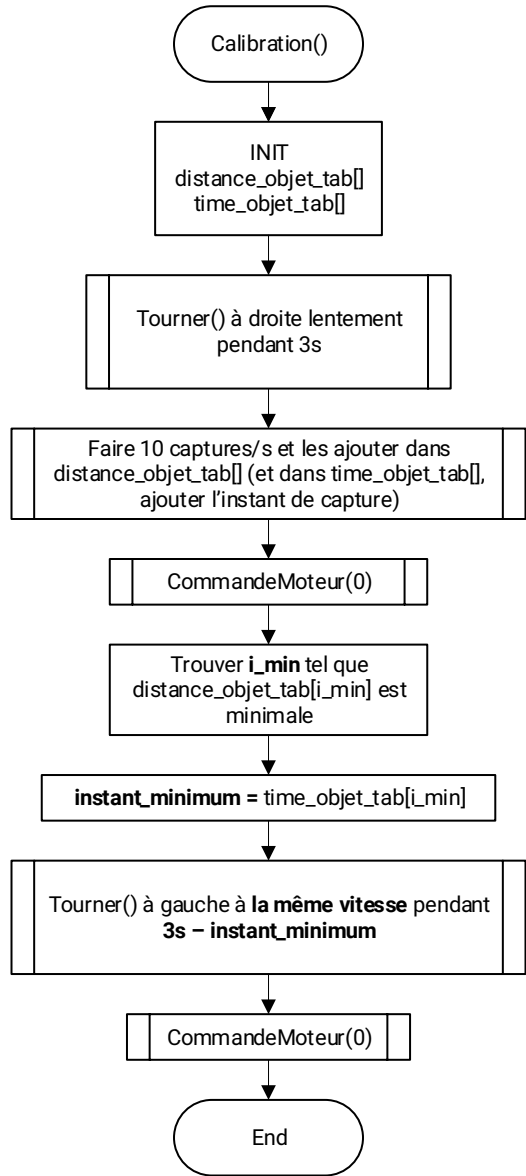
VARIABLE GLOBALES:
- ETAT = {NOT_START, START, CALIB, RUN}
- VOLTAGE = valeur décimale
- DISTANCE_OBJET = valeur décimale



Traitement



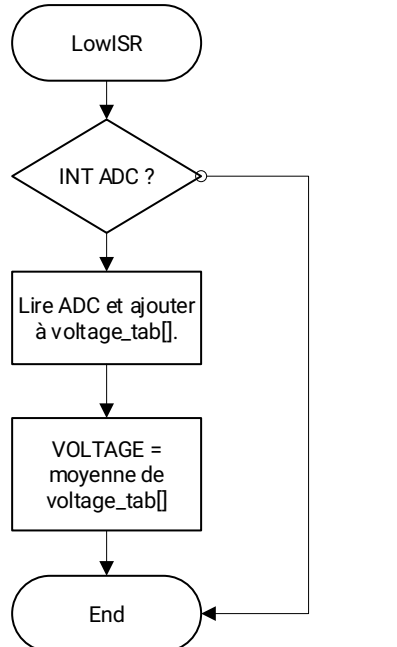
Aligner l'axe du robot avec la cible



Interruptions

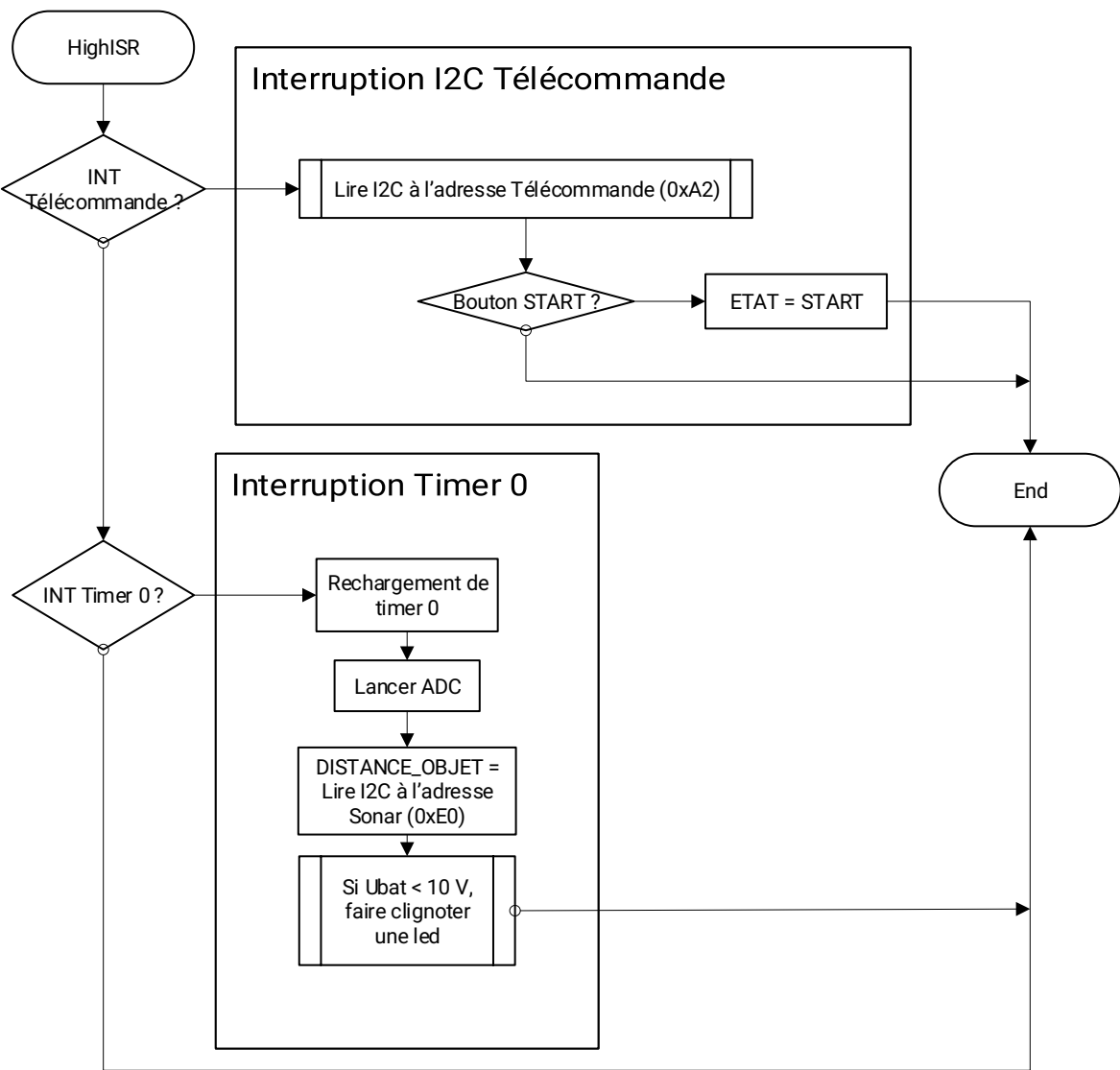
On assume qu'il y a acquittement de l'interruption.

Interruption basse priorité

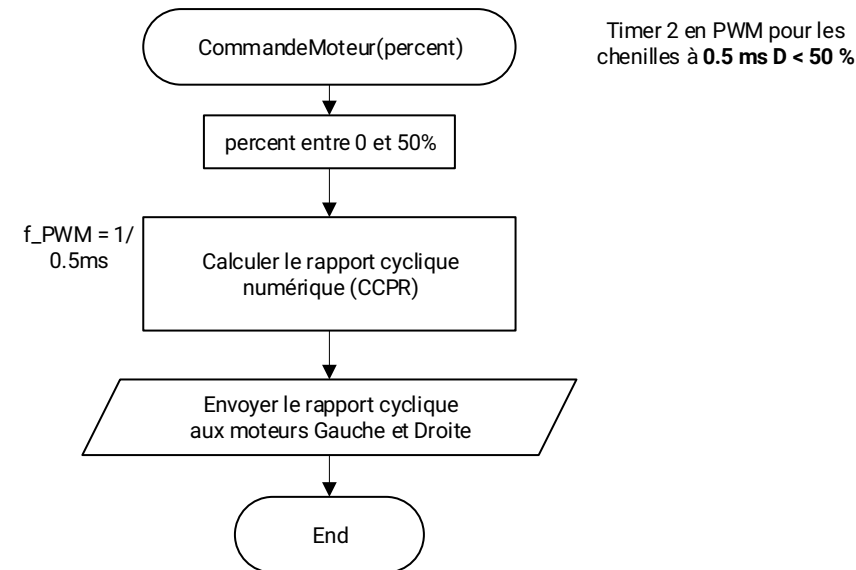


Variables globales statique:
- voltage_tab[8] // Sauvegardes de 8 valeurs de VOLTAGE

Interruption haute priorité

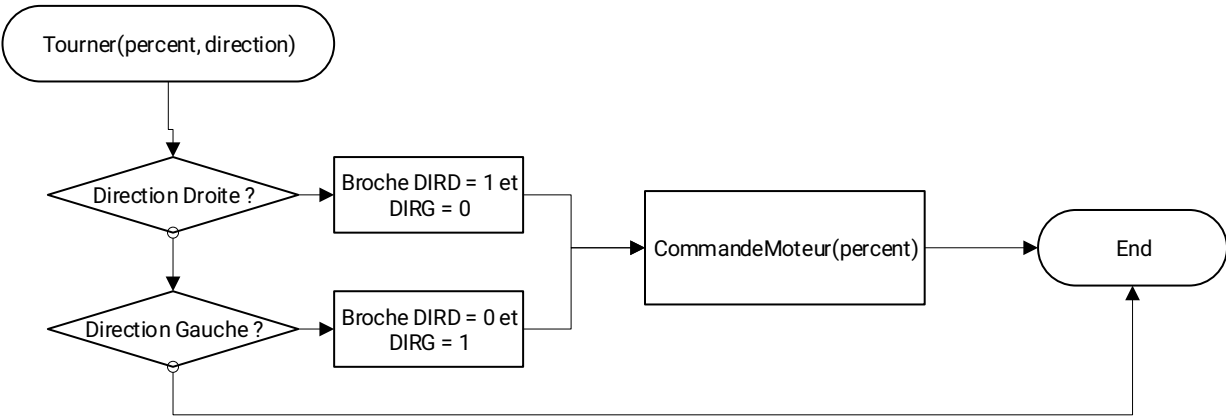


Commander en vitesse



Timer 2 en PWM pour les chenilles à 0.5 ms D < 50 %

Tourner



Avancer

