main.cpp File Reference

```
#include <stdlib.h>
#include <avr/io.h>
#include <avr/wdt.h>
#include <avr/interrupt.h>
#include <string.h>
#include "FreeRTOS.h"
#include "task.h"
#include "queue.h"
#include "croutine.h"
#include "rs232int.h"
#include "time_stamp.h"
#include "frt_task.h"
#include "frt_text_queue.h"
#include "frt_queue.h"
#include "frt_shared_data.h"
#include "shares.h"
#include "xmega_util.h"
#include "task_user.h"
#include "task_LED.h"
#include "task_MOTOR.h"
#include "task_EdgeSense.h"
```

Functions

frt_text_queue	**print_ser_queue** (32, NULL, 10)
int	**main** (void)

Variables

shared_data< bool > *	**IR_flg**

Detailed Description

This file contains the **main()** code for a program which runs a port of the FreeRTOS for AVR devices for a sumo robot. This port is specific to the XMEGA family. License: This file is released under the Lesser GNU Public License, version 2. This program is intended for educational use only, but it is not limited thereto.

Function Documentation

◆ main()

int main (void   )

The main function sets up the RTOS. Some test tasks are created. Then the scheduler is started up; the scheduler runs until power is turned off or there's a reset.

Returns

This is a real-time microcontroller program which doesn't return. Ever.

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