```
#include "Main.h"
void move ( void )
{
    int temp;
    int steer;
    int error;
    int speed;
    error=4-max_no-1; // heading direction error, if PD4 ==max_no, no error; - 1 is to stop it from veering to the righ¬
    t
    steer=error*steer_sensitivity; // steering effort is proportional to heading error
    speed=forward_speed; // forward speed
    if ( PD_sum<ambient_level ) // If <background noise level => search mode.
    {
        speed=0; // search mode => no forward motion
        steer=spin_speed; // search mode => spin
    }
    if ( PD_sum>slow_level ) // Beacon is near!
    {
        speed=slow_speed; // Slow down
    }
    if ( PD_sum>stop_level ) // Found the beacon!
    {
        speed=0; // Stop
        steer=0; // no steering
    }
    temp=limit_pwm(0+steer+speed);
    SetMotor ( 1 , temp ) ;
    temp=limit_pwm(0+steer-speed);
    SetMotor ( 10 , temp ) ;
}
```