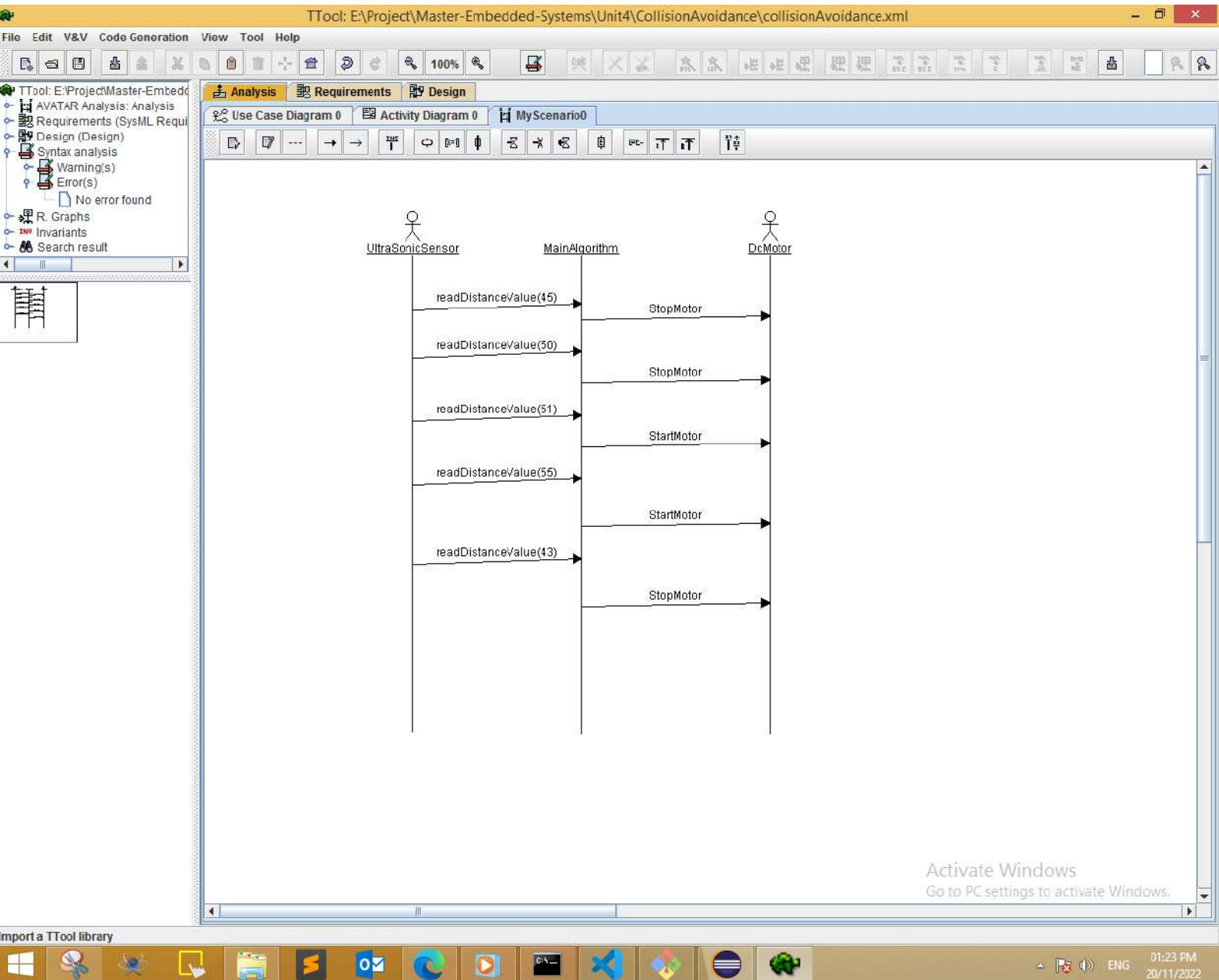
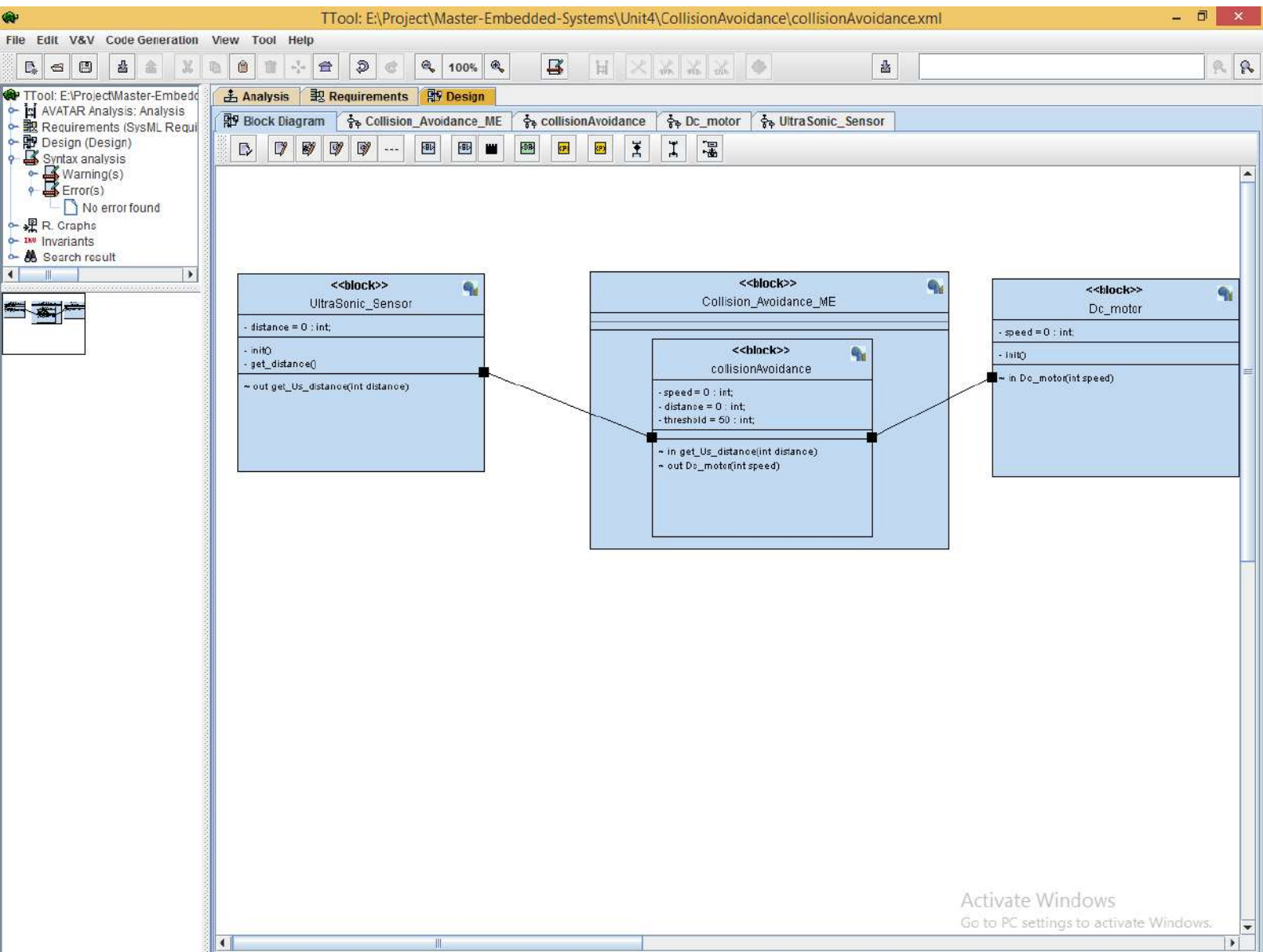
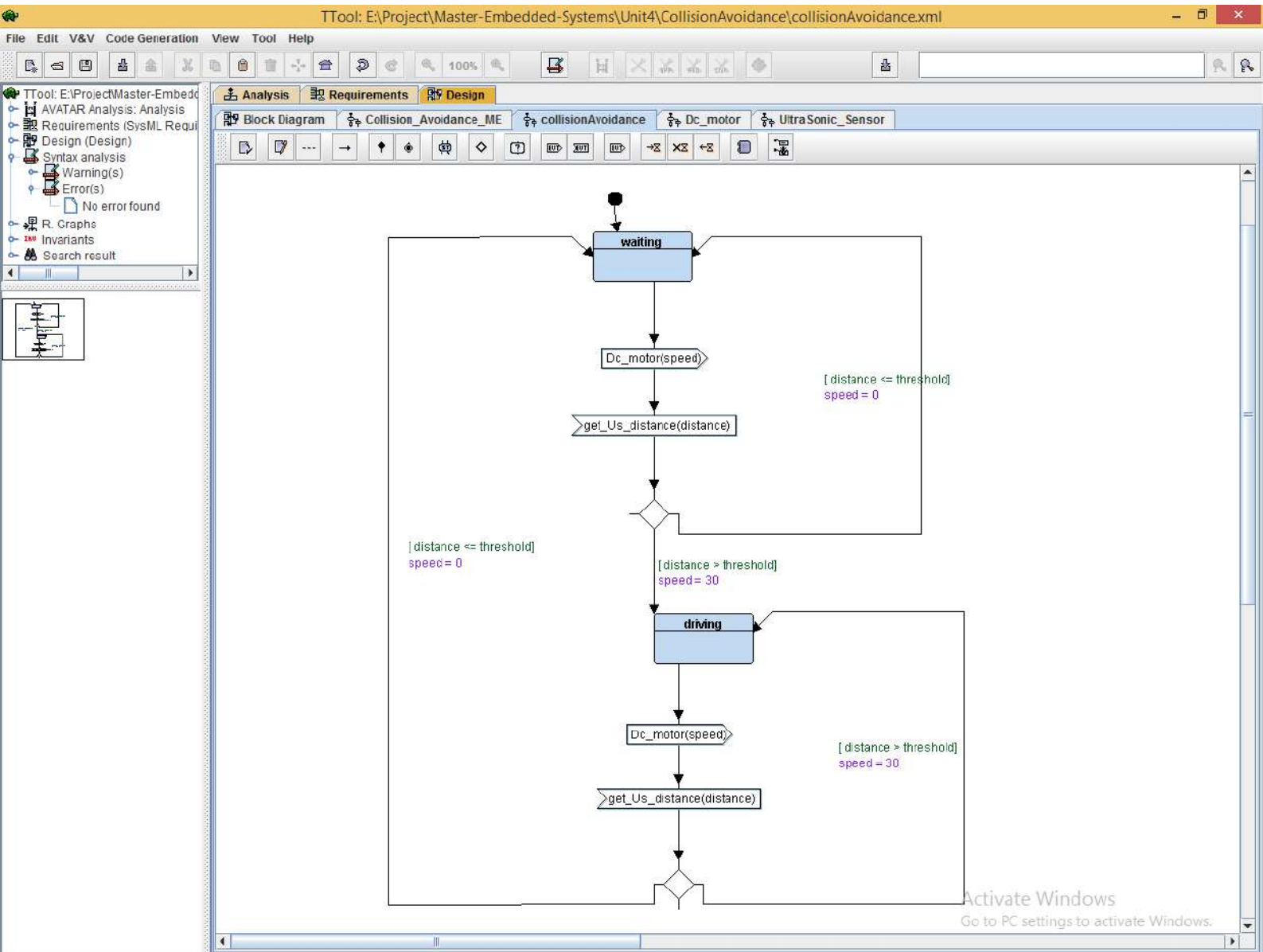


Save an opened or a new TTool modeling



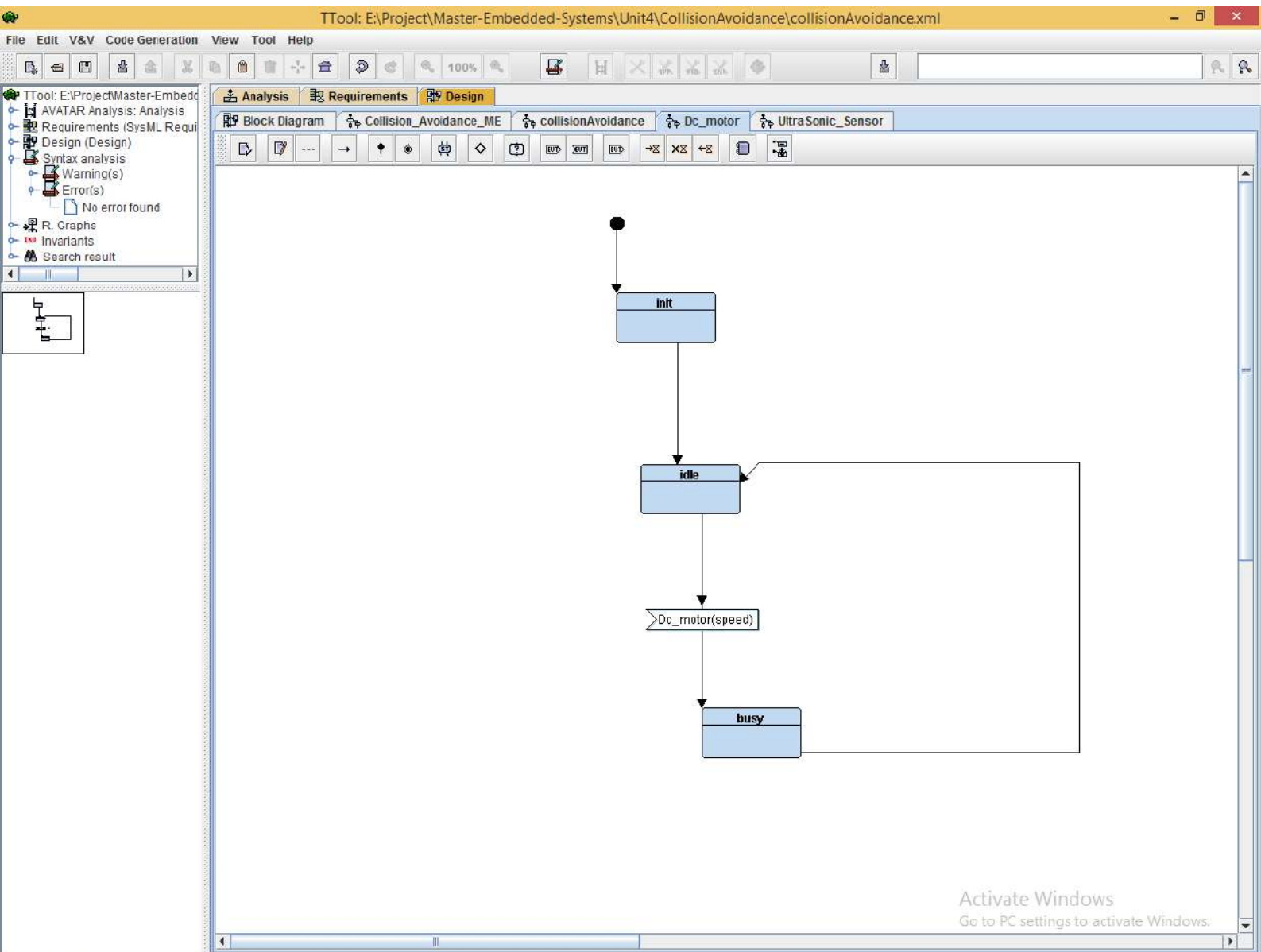


Paste - if possible - previously cut / copied components at the minimal position of the currently opened diagram

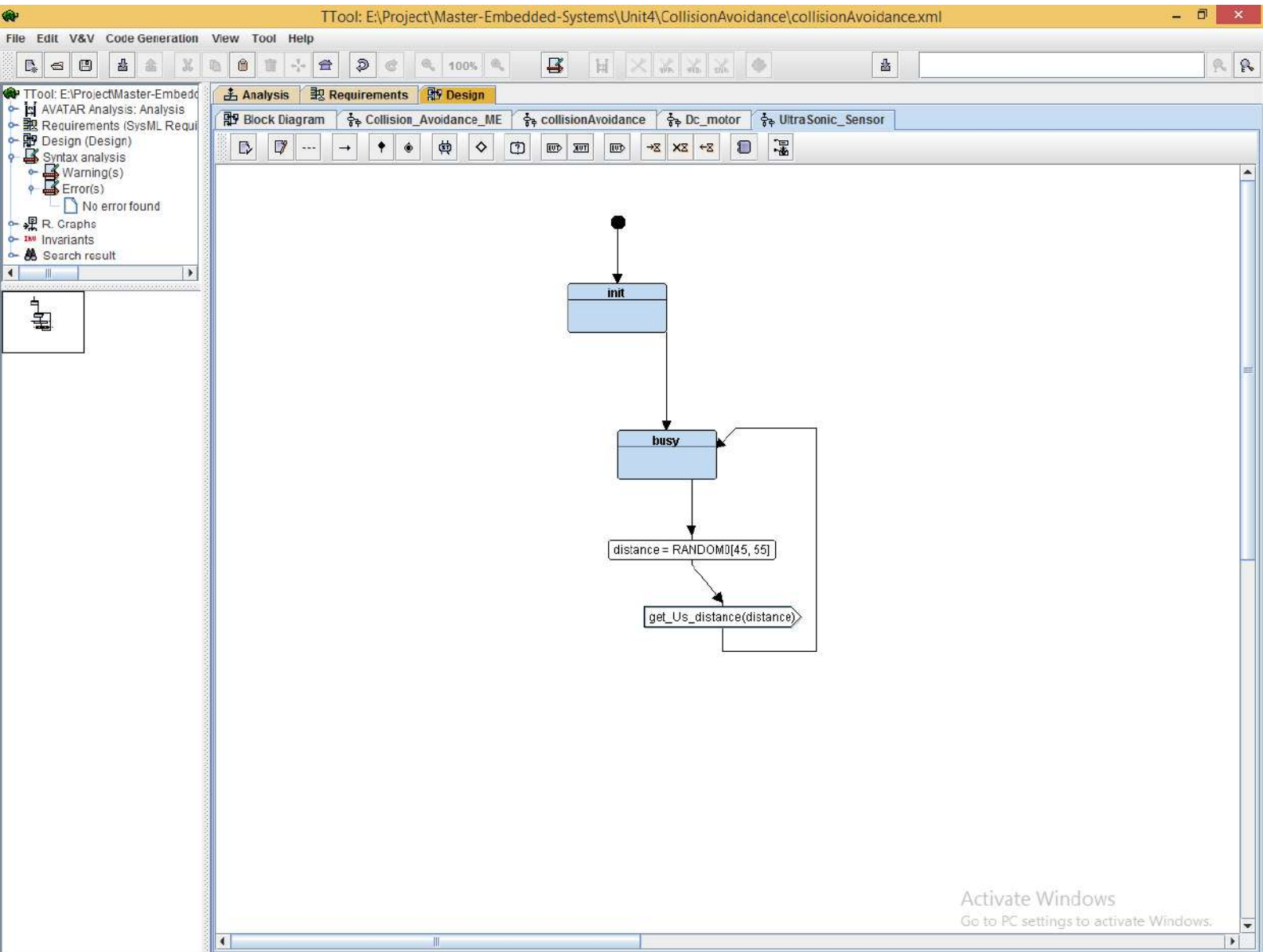


Delete selected components





Copy selected components





File Edit Selection View Go Run Terminal Help

Project

EXPLORER

- PROJECT
  - extensions.json
  - launch.json
  - settings.json
  - tasks.json
  - dosingMachine
  - FIFO
  - FIFO\_test
  - LIFO
  - LIFO\_buffer
  - Master-Embedded-Systems
    - t8cd
      - CA\_Unit4\_lesson2\_3\_modules
        - CA.c
        - CA.h
        - Dc\_motor.c
        - Dc\_motor.h
        - main.c
        - state.h
        - Us.c
        - Us.h
        - fifo\_test
        - Lesson2\_CA\_V1
      - Unit2
      - Unit3
      - Unit4
        - CollisionAvoidance
          - collision\_avoidance.c
          - collision\_avoidance.h
          - collision\_avoidance.o
          - dc\_motor.c
          - dc\_motor.h
          - dc\_motor.o
          - hellomake.exe
          - main.c
          - main.o
          - makefile
          - state.h
          - us\_sensor.c

Master-Embedded-Systems > Unit4 > CollisionAvoidance > collision\_avoidance.c > STATE\_define(CA\_driving)

```
12 fflush(stdout);
13 (CA_distance <= CA_threshold) ? (CA_state = STATE(CA_waiting)) : (CA_state = STATE(CA_driving));
14 }
15
16 STATE_define(CA_waiting)
17 {
18     //State name
19     CA_State_id = CA_waiting;
20     //state action
21     CA_speed = 0;
22     DC_motor(CA_speed);
23     printf("CA_waiting_state: distance = %d speed = %d\n", CA_distance, CA_speed);
24     fflush(stdout);
25 }
26
27 STATE_define(CA_driving)
28 {
29     //State action
30     CA_State_id = CA_driving;
31     CA_speed = 30;
32     printf("CA_waiting_state: distance = %d speed = %d\n", CA_distance, CA_speed);
33     fflush(stdout);
34
35     DC_motor(CA_speed);
36 }
```

PROBLEMS OUTPUT DEBUG CONSOLE TERMINAL JUPYTER GITLENS

bash

```
DC busy state speed = 0
Us_busy State: distance = 53
Us_sensor ---distance = 53---> CA_algorithm
CA_waiting_state: distance = 53 speed = 30
CA ---speed = 30--->DC_motor
DC busy state speed = 30
Us_busy State: distance = 45
Us_sensor ---distance = 45---> CA_algorithm
CA ---speed = 0----->DC_motor
CA_waiting_state: distance = 45 speed = 0
DC busy state speed = 0
Us_busy State: distance = 55
Us_sensor ---distance = 55---> CA_algorithm
CA_waiting_state: distance = 55 speed = 30
CA ---speed = 30--->DC_motor
DC busy state speed = 30
Us_busy State: distance = 46
Us_sensor ---distance = 46---> CA_algorithm
```

Activate Windows  
Go to PC settings to activate Windows.