**Définitions et fonctions principaux :**

**typedef** **enum** {

*FORWARD* = HIGH, *BACK* = LOW

} direction;

**typedef** **enum** {

*motorA* = 0, *motorB* = 1

} motor;

**typedef** **enum** {

*optoA* = 0, *optoB* = 1

} opto;

**typedef** **enum** {

*irA* = 0, *irA* = 1, *irC* = *2*

} irSensor;

**void** **initRobot**();

**void** **setMortorSpeed**(motor motor, **int** speed);

**void** **setMortorDirection**(motor motor, direction d);

**int** **readOpto**(opto opto);

**void** **goForward**(**int** speed);

**void** **goBack**(**int** speed);

**void** **turnLeft**(**int** speed);

**void** **turnRight**(**int** speed);

**void** **goForwardTurn**(**int** speedA, **int** speedB);

**void** **goBackTurn**(**int** speedA, **int** speedB);

**void** **stopRobot**();

**void** **ajustGoFoward**(uint16\_t a, uint16\_t b, uint8\_t speed);

**int** **readIR**(irSensor irSensor);