Lab1

void main() {

TRISB = 0x00;

PORTB = 0x00;

while(1){

PORTB.F0 = 0xff;

delay\_ms(1000);

PORTB.F0 = 0x00;

delay\_ms(1000);

}

}

Lab -2  
void main() {

TRISB = 0;

PORTB = 0;

while(1){

PORTB = 0x01;

Delay\_ms(1000);

PORTB = 0x02;

Delay\_ms(1000);

PORTB = 0x04;

Delay\_ms(1000);

PORTB = 0x08;

Delay\_ms(1000);

PORTB = 0x10;

Delay\_ms(1000);

PORTB = 0x20;

Delay\_ms(1000);

PORTB = 0x40;

Delay\_ms(1000);

PORTB = 0x80;

Delay\_ms(1000);

PORTB = 0xFF;

Delay\_ms(2000);

PORTB = 0x00;

Delay\_ms(2000);

}

}

Lab 3 code

void main() {

int status=0;

TRISB = 0x00; //Set portb as output

TRISD = 0xff; //set portd as input

PORTB = 0x00; //portb initialization

while(1){

//Forward Button

if(PORTD.f0 == 1){

delay\_ms(200);

if(PORTD.f0 == 1){

status = 1;

}

}

//Stop Buttopn

if(portd.f3 == 1){

delay\_ms(200);

if(PORTD.f3 == 1){

status = 0;

}

}

//Reverse Button

if(portd.f6 == 1){\

delay\_ms(200);

if(PORTD.f6 == 1){

status = 2;

}

}

//Mototr moving as status direction

if (status == 1){

portb.f0 = 1;

portb.f1 = 0;

}

else if (status == 2){

portb.f0 = 0;

portb.f1 = 1;

}

else{

portb.f0 = 0;

portb.f1 = 0;

}

}

}