harry code

I follow LSRB Algorithm which L stands for 'LEFT', S for 'STRAIGHT', R for RIGHT, and B for 'BACK' or BACKWARD.

These LEFT, RIGHT, STRAIGHT, and BACK are the directions that the robot follows.

In this algorithm LEFT direction has the highest priority and the BACK direction has the least priority.

EXPLANATION :

Step 1: Always follow LEFT whenever there is a turn possible

Step 2: If LEFT is not possible go STRAIGHT.

Step 3: If LEFT and STRAIGHT both are not possible take RIGHT.

Step 4: if LEFT, STRAIGHT, and RIGHT are not possible go BACK.

Safe code :

I used 3 Encoder & wrote declaration of 6 signal .

I found 3 counter for each encoder .

I found angle of each encoder in degree by using this equation (counter*360)/(PPR*4) ,which PPR refers to pulse per revolution.

I used 4 as there are 2 signal & the mode of interrupt is change(2*2)=4.

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