#include <avr/io.h>

#include <util/delay.h>

#define MOTOR\_PIN\_1 0 // Motor control pin 1 (e.g., PC0)

#define MOTOR\_PIN\_2 1 // Motor control pin 2 (e.g., PC1)

void motor\_init() {

DDRC|= (1 << MOTOR\_PIN\_1) | (1 << MOTOR\_PIN\_2); // Set motor control pins as output

}

void motor\_forward() {

PORTC |= (1 << MOTOR\_PIN\_1); // Set pin 1 high

PORTC&= ~(1 << MOTOR\_PIN\_2); // Set pin 2 low

}

/\*void motor\_reverse() {

PORTC&= ~(1 << MOTOR\_PIN\_1); // Set pin 1 low

PORTC |= (1 << MOTOR\_PIN\_2); // Set pin 2 high

}\*/

/\*void motor\_stop() {

PORTC&= ~((1 << MOTOR\_PIN\_1) | (1 << MOTOR\_PIN\_2)); // Set both pins low

}\*/

int main(void) {

motor\_init(); // Initialize motor pins

while (1) {

motor\_forward(); // Run motor forward

*\_delay\_ms*(1000); // Delay 1 second

//motor\_stop(); // Stop motor

//\_delay\_ms(1000); // Delay 1 second

//motor\_reverse(); // Run motor in reverse

//\_delay\_ms(1000); // Delay 1 second

//motor\_stop(); // Stop motor

//\_delay\_ms(1000); // Delay 1 second

}

return 0;

}