/\* simar 20/4/10

the robot arm works fine forward and reverse regaining its

origional position.

now the connection with parallel port of pc is required..

\*/

#define F\_CPU 12000000UL

#include<avr/io.h>

#include<util/delay.h>

int main()

{

char i=0,j,k;

DDRD=0xFF;

DDRB=0xFF;

DDRC=0xFF;

for(k=0;k<10;k++)

{

// forward

i=0;

for(j=0;j<8;j++) //to create 8 steps

{

PORTD=1<<(i);

\_delay\_ms(20);

i++;

if (i==4) i=0;

}

i=0;

\_delay\_ms(150);

for(j=0;j<8;j++)

{

PORTC=1<<(i);

\_delay\_ms(20);

i++;

if (i==4) i=0;

}

i=0;

\_delay\_ms(150);

for(j=0;j<8;j++)

{

PORTB=2<<(i);

\_delay\_ms(20);

i++;

if (i==4) i=0;

}

\_delay\_ms(150);

//backward

i=3;

for(j=0;j<8;j++)

{

PORTB=2<<(i); //according to the pind of port b used

\_delay\_ms(20);

if (i==0) i=4;

i--; //this is done intentiolly as a logic

}

\_delay\_ms(150);

i=3;

for(j=0;j<8;j++)

{

PORTC=1<<(i);

\_delay\_ms(20);

if (i==0) i=4;

i--;

}

\_delay\_ms(150);

i=3;

for(j=0;j<8;j++)

{

PORTD=1<<(i);

\_delay\_ms(20);

if (i==0) i=4;

i--;

}

\_delay\_ms(150);

}

}