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Control of Mobile Robots
Project 6

HALF_STEP_REV(steps, direction)

count_both <= steps — no → count_both = 0 → return

yes

Interruptcount_right >= top_speed && interruptcount_left >= top_speed

Write step to port B, Increment or decrement based on direction of turn, interruptcount_left = interruptcount_right = 0, count_both++

RAMP_BOTH_DOWN_REV(steps, direction)

count_both <= steps — no → current_speed = bottom_speed, count_both = 0 → return

yes

current_speed >= bottom_speed

no

yes

Interruptcount_right >= current_speed && interruptcount_left >= current_speed

Write step to port B, Increment or decrement based on direction of turn, interruptcount_left = interruptcount_right = 0, current_speed++, count_both++

RAMP_BOTH_UP_REV(steps, direction)

count_both <= steps — no → current_speed = top_speed, count_both = 0 → return

yes

current_speed >= top_speed

no

yes

Interruptcount_right >= current_speed && interruptcount_left >= current_speed

Write step to port B, Increment or decrement based on direction of turn, interruptcount_left = interruptcount_right = 0, current_speed--, count_both++