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#include "MeMegaPi.h"
#include "MeDCMotor.h"
#include "MeEncoderMotor.h"

const byte interruptPin =18;
const byte NE1=31;
long count=0;
unsigned long time;
unsigned long last_time;
MeMegaPiDCMotor motor1(PORT1B);
MeMegaPiDCMotor motor2(PORT2B)
uint8_t motorSpeed = 185;
uint8_t motorSpeed2 = 100;
uint8_t motorSpeed3 = 50;

void setup()
{
    pinMode(interruptPin, INPUT_PULLUP);
    pinMode(NE1, INPUT);
    attachInterrupt(digitalPinToInterrupt(interruptPin), blink,RISING);
    Serial.begin(9600);
}
void loop()
{
    motor1.run(motorSpeed);          // value: between -255 and 255
    motor2.run(motorSpeed2);
    time =millis();
    if(time-last_time>2000)
    {
        Serial.println(count);
        last_time=time;
    }
}
void blink()
{
    if (digitalRead(NE1)>0)
        count++;
    else
        count = count - 1;
}
```