```
#include "motor.h"
#include "interface.h"
#include "stm32f10x.h"

//GPIO配置函数
void MotorGPIO_Configuration(void)
{
    GPIO_InitTypeDef GPIO_InitStructure;
    GPIO_InitStructure.GPIO_Pin  =  LEFT_F_PIN  |  LEFT_B_PIN  |  RIGHT_F_PIN  |
RIGHT_B_PIN;

    GPIO_InitStructure.GPIO_Speed = GPIO_Speed_2MHz;
    GPIO_InitStructure.GPIO_Mode = GPIO_Mode_Out_PP;
    GPIO_Init(LEFT_F_GPIO, &GPIO_InitStructure);
}

//根据占空比驱动电机转动
void CarMove(void)
{
    //左轮
    if(left_speed_duty > 0)//向前
    {
        if(speed_count < left_speed_duty)
        {
            LEFT_GO;
        }else
        {
            LEFT_STOP;
        }
    }
    else if(left_speed_duty < 0)//向后
    {
        if(speed_count < (-1)*left_speed_duty)
        {
            LEFT_BACK;
        }
        else
        {
            LEFT_STOP;
        }
    }
    else                //停止
    {
        LEFT_STOP;
```

```
    }

    //右轮
    if(right_speed_duty > 0)//向前
    {
        if(speed_count < right_speed_duty)
        {
            RIGHT_GO;
        }
        else                //停止
        {
            RIGHT_STOP;
        }
    }
    else if(right_speed_duty < 0)//向后
    {
        if(speed_count < (-1)*right_speed_duty)
        {
            RIGHT_BACK;
        }
        else                //停止
        {
            RIGHT_STOP;
        }
    }
    else                //停止
    {
        RIGHT_STOP;
    }
}

//向前
void CarGo(void)
{
    left_speed_duty=MAX_SPEED_DUTY;
    right_speed_duty=MAX_SPEED_DUTY;
}
//需向右向前
void CarGoL(void)
{
    left_speed_duty=MAX_SPEED_DUTY;
    right_speed_duty=MAX_SPEED_DUTY-15;
}
//需向左向前
```

```
void CarGoR(void)
{
    left_speed_duty=MAX_SPEED_DUTY-15;
    right_speed_duty=MAX_SPEED_DUTY;
}

void MotorInit(void)
{
    MotorGPIO_Configuration();
}
```