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/*****
Cod robot line follower

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*****/

#include <stdlib.h>
#include <avr/io.h>
#include <avr/interrupt.h>
#include <util/delay.h>

void get_sensors(){
    if(PINC==0x00 || PINC==0xFF){
        //oprim motoarele;
        PORTB = (1<<PB6) | (1<<PB7);
    }
    else{
        if((PINC & (1<<PC3))==1 || (PINC & (1<<PC4))) {
            PORTB = (1<<PB6) | (1<<PB7) | (1<<PB2) | (1<<PB4);
        }
        else if((PINC & (1<<PC1))==1 || (PINC & (1<<PC2))) {
            PORTB = (1<<PB6) | (1<<PB7) | (1<<PB2);
        }
        else if(PINC & (1<<PC0)){
            PORTB = (1<<PB6) | (1<<PB7) | (1<<PB2);
            _delay_us(100);
        }
        else if((PINC & (1<<PD7))) {
            PORTB = (1<<PB6) | (1<<PB7) | (1<<PB4);
            _delay_us(100);
        }
        else{
            PORTB = (1<<PB6) | (1<<PB7) | (1<<PB4);
        }
    }
}

int main(){
    sei();
    DDRC = 0x00;
    DDRB = 0xFF;
    PORTB = (1<<PB6) | (1<<PB7);
    PORTC = 0xFF; //activam rezistentele de pull-up
    DDRC = 0x00;
    while(1){
        get_sensors();
    }
    return 0;
}

```