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/*****
Cod robot line follower

Culea Cristian 331CA
Turlea Catalina 331CA
*****/

#include <avr/io.h>
#include <avr/interrupt.h>

#define F_CPU 16000000
#include <util/delay.h>
#include <stdlib.h>
#define INPUT1 0
#define INPUT2 1
#define INPUT3 3
#define INPUT4 4
#define ENABLEA 2
#define ENABLEB 5

void get_sensors(){
    if(PINC==0x00||PINC==0xFF){
        //oprim motoarele;
        PORTB=(1<<PB6)|(1<<PB7);
    }
    else{
        if((PINC&(1<<PC3))==1 || (PINC&(1<<PC4))) {
            //mergem inainte
            PORTB=(1<<PB6)|(1<<PB7)|(1<<PB2)|(1<<PB4);
        }
        else if((PINC&(1<<PC1))==1 || (PINC&(1<<PC2))) {
            //facem stanga
            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;//rezistente de pull up
    DDRC=0x00;
    while(1){
        get_sensors();
    }
    return 0;
}

```