```
#include <avr/io.h>
#include "usart.h"

#define UP_S 'A'
#define DOWN_S 'C'
#define LEFT_S 'D'
#define RIGHT_S 'B'
#define STOP 'F'

void init_pins()
{
	//motoare
   DDRC |= (1 << PC0);
   DDRC |= (1 << PC1);
   DDRC |= (1 << PC2);
   DDRC |= (1 << PC3);

	DDRD |= (1 << PD7);

	sei();
}

void turn_left()
{
	PORTC |= (1 << PC1);
	PORTC &= ~(1 << PC0);
	PORTC |= (1 << PC2);
	PORTC &= ~(1 << PC3);
}

void turn_right()
{
	PORTC |= (1 << PC0);
	PORTC &= ~(1 << PC1);
	PORTC |= (1 << PC3);
	PORTC &= ~(1 << PC2);
}

void forward()
{
	PORTC |= (1 << PC0);
	PORTC &= ~(1 << PC1);
	PORTC |= (1 << PC2);
	PORTC &= ~(1 << PC3);
}

void backward()
{
   PORTC |= (1 << PC1);
	PORTC &= ~(1 << PC0);
	PORTC |= (1 << PC3);
```

```
	PORTC &= ~(1 << PC2);
}

void stop()
{
	PORTC &= ~(1 << PC0);
	PORTC &= ~(1 << PC1);
	PORTC &= ~(1 << PC3);
	PORTC &= ~(1 << PC2);
}

ISR(USART0_RX_vect) {
	char c = USART0_receive();

	switch (c) {
		case UP_S:
			forward();
			break;

		case DOWN_S:
			backward();
			break;

		case RIGHT_S:
		case RIGHT_L:
			turn_right();
			break;

		case LEFT_S:
		case LEFT_L:
			turn_left();
			break;

		case STOP:
			stop();
			break;
	}
}


int main(void)
{
	init_pins();
	USART0_init();
	PORTD |= (1 << PD7);

	while(1) {}
	cli();

	return 0;
}
```