

**ภาคผนวก จ.**

**โปรแกรมของหุ่นยนต์ (ภาครับ)**

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#include <18f458.h>
#fuses H4, NOWDT, NOLVP, NOBROWNOUT
#use delay(clock=4000000)
#use rs232(baud=9600, xmit=PIN_C6, rcv=PIN_C7) // Jumpers: 8 to 11, 7 to 1

main()
{
char value;
output_d(0b00000000);
output_b(0b00000000); //Initial condition
while (true)
{
value = getc();
if (value == 'w')
output_d(0b00000001); //Forward
else if (value == 's')
output_d(0b00000100); //Backward
else if (value == 'a')
output_d(0b01000000); //Right
else if (value == 'd')
output_d(0b00010000); //Left
else if (value == 'i')
output_d(0b10000000); //Hold tire
else if (value == 'k')
output_d(0b00100000); //Release tire
else if (value == 'u')
output_d(0b00000010); //Up tire
else if (value == 'j')
output_d(0b00001000); //Down tire
else if (value == 'f')
output_b(0b00000001); //Tilt left camera
else if (value == 'h')
output_b(0b00000100); //Tilt right camera
else if (value == 't')
output_b(0b00000010); //Pan up camera
else if (value == 'g')
output_b(0b00001000); //Pan down camera
else if (value == 'z')
output_high(pin_C0); //Open camera 2
else if (value == 'x')
output_low(pin_C0); //Close camera 2
else if (value == 'c')
output_high(pin_C2); //Open camera 1
else if (value == 'v')
output_low(pin_C2); //Close camera 1
else if (value == 'o')

```

```
output_high(pin_C1);           //Open lamp 2
else if (value == '1')
output_low(pin_C1);           //Close lamp 2
else if (value == 'b')
output_high(pin_C3);          //Open lamp 1
else if (value == 'n')
output_low(pin_C3);          //Close lamp 1
else
{
output_d(0b00000000);
output_b(0b00000000);
}
}
}
```