

cololuQTRSensors.h orangutan.h delay.h OrangutanTime.h TW_Master_main.c Liniensensorsteuerung main.cpp ASF Wizard

```

#include <pololu/orangutan.h>

int main()
{
    // initialize your QTR sensors
    unsigned char qtr_rc_pins[] = {IO_C0, IO_C1, IO_C2};
    qtr_rc_init(qtr_rc_pins, 3, 2000, 255); // 800 us timeout, no emitter pin
    // int qtr_analog_pins[] = {0, 1, 2};
    // qtr_analog_init(qtr_analog_pins, 3, 10, IO_C0); // 10 samples, emitter pin is PC0
    // optional: wait for some input from the user, such as a button press

    // then start calibration phase and move the sensors over both
    // reflectance extremes they will encounter in your application:
    int i;
    for (i = 0; i < 250; i++) // make the calibration take about 5 seconds
    {
        qtr_calibrate(QTR_EMITTERS_ON);
        delay(20);
    }

    // optional: signal that the calibration phase is now over and wait for further
    // input from the user, such as a button press

    while (1)
    {
        // main body of program goes here
    }

    return 0;
}

```

20 %

Error List

Entire Solution 5 Errors 0 Warnings 0 Messages Build + IntelliSense

Description	Project	File
ld returned 1 exit status	Liniensensorsteuer collect2.exe	ung
recipe for target 'Liniensensorsteuer.elf' failed	Liniensensorsteuer	Makefile
undefined reference to 'delay_ms'	Liniensensorsteuer	OrangutanTir
undefined reference to 'qtr_calibrate'	Liniensensorsteuer	main.cpp
undefined reference to 'qtr_rc_init'	Liniensensorsteuer	main.cpp

Solution Explorer

Solution 'Liniensensorsteuerung' (1 project)

- Dependencies
 - 3pi.h
 - common.h
 - delay.h
 - Delay.h
 - delay_basic.h
 - fuse.h
 - General.h
 - interrupt.h
 - iintypes.h
 - io.h
 - iom32.h
 - lock.h
 - math.h
 - orangutan.h
 - OrangutanAnalog.h
 - OrangutanBuzzer.h
 - OrangutanDigital.h
 - OrangutanLCD.h
 - OrangutanLED.h
 - OrangutanModel.h
 - OrangutanMotors.h
 - OrangutanTime.h

Properties

Liniensensorsteuerung Project Properties