```c
#include "asuro.h"

int main(void)
{
        Init();
//allgemeine Funktionen

        //variable Msleep in 1ms Schritten
        int Msleep (unsigned int b) {
                unsigned int i;
                i = 0;
                while (i<b) {
                        Sleep (72);
                        i++;
                }
                return 1;
        }

        //Blinker (MotorSpeed(FWD-0,RWD-125) für 90° Drehung)
        int Blink (char s) {
                char i;
                for(i=0;i<5;i++) {
                        if (s==1) {
                                BackLED(OFF,ON);
                                Msleep(110);
                                BackLED(OFF,OFF);
                                Msleep(110);
                        } else if (s==0) {
                                BackLED(ON,OFF);
                                Msleep(110);
                                BackLED(OFF,OFF);
                                Msleep(110);
                        } else {
                                BackLED(ON,ON);
                                Msleep(110);
                                BackLED(OFF,OFF);
                                Msleep(110);
                        }
                }
                return 1;
        }

        //Langsames Anfahren
        int Anfahren (unsigned char max) {
                unsigned char speed;
                for (speed=70;speed<max;speed++) {
                        MotorSpeed(speed-4,speed);
                        Msleep(10);
                }
                return 1;
        }

        //Drehen um +/- 90 Grad
        int Drehen (char grad) {
                //Kleiner Rangierabstand
                BackLED(ON,ON);
                MotorDir(RWD,RWD);
                MotorSpeed(166,170);
                Msleep(650);
                MotorDir(BREAK,BREAK);
                MotorSpeed(0,0);
                Msleep(50);
                MotorDir(FREE,FREE);
                BackLED(OFF,OFF);
                Msleep(250);
                //Drehen
                if (grad==1) {
                        MotorDir(FWD,RWD);
```

```c
                        MotorSpeed(0,127);
                        Blink(0);
                        MotorDir(BREAK,BREAK);
                        MotorSpeed(0,0);
                }

                if (grad==0) {
                        MotorDir(RWD,FWD);
                        MotorSpeed(127,0);
                        Blink(1);
                        MotorDir(BREAK,BREAK);
                        MotorSpeed(0,0);
                }
                StatusLED(YELLOW);
                Msleep(100);

                return 1;
        }

//HAUPTPROGRAMM
        char taster1;
        char taster2;
        char taster;

for (;;) {

        taster1=0;
        taster2=0;
        taster=0;

        StatusLED (GREEN);
        MotorDir(FWD,FWD);
        Anfahren(200);

//Abfrage der Taster
do {
        taster1 = PollSwitch();
        Msleep(4);
        taster2 = PollSwitch();

        MotorSpeed(200,200);

        if (taster1==taster2) {
                taster=(taster1+taster2)/2;
        } else {
                taster=0;
        }
        }
while (taster==0);

        StatusLED (RED);
        MotorSpeed(0,0);
        Msleep(20);

if (taster>=8) { Drehen(1); }
else { Drehen(0); }

}
//ENDE
        while(1);
        return 0;
}
```