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                                main.c

/* =====
 *
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 *
 * =====
*/
#include <project.h>

int main()
{
    CyGlobalIntEnable; /* Enable global interrupts. */
    Clock_1_Enable();

    I2C_MOTOR_Start();
    QuadDec_X_Start();
    QuadDec_Y_Start();
    QuadDec_Z_Start();
    int32 X_counterValue = 0;
    //int32 Y_counterValue = 0;
    //int32 Z_counterValue = 0;

    uint8 waarde[3] = {0x2, 0x2, 0x2};

    //waarde[0]=0x0;
    //waarde[1]=0x3F;
    //waarde[2]=0x20;

    int MOTOR_I2C_SLAVEADRES = 0xB0;
    uint8 bufsize = 4;
    /* Place your initialization/startup code here (e.g. MyInst_Start()) */

    for(;;)
    {
        X_counterValue = QuadDec_X_GetCounter();
        //Y_counterValue = QuadDec_Y_GetCounter();
        //Z_counterValue = QuadDec_Z_GetCounter();
        if (X_counterValue <= 50000) {
            LEDTC_Write(1);
            I2C_MOTOR_MasterClearStatus(); /* Clear any previous status */
            I2C_MOTOR_MasterWriteBuf(MOTOR_I2C_SLAVEADRES, waarde, bufsize,
, I2C_MOTOR_MODE_COMPLETE_XFER);
            for(;;) { if(0u != (I2C_MOTOR_MasterStatus() &
I2C_MOTOR_MSTAT_WR_CMPLT)) { /* Transfer complete. Check
Master status to make sure that transfer completed without errors
. */

                break;
            }
        }
        if (X_counterValue > 50000 ) {

```

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main.c
    LEDTC_Write(0);
}
/* Place your application code here. */
}
}
/* [] END OF FILE */
```