```c
#include "simpletools.h" // Include simple tools
#include "servo360.h"
#include "adcDCpropab.h"

int l_ar[52];
int r_ar[52];
int n = 1;
void sd_handle();
void navigate();
int main() // Main function
{

pause(100);
navigate();
pause(500);
sd_handle();
}

void sd_handle(){
int left_ds;
int right_ds;
while(n < 48){
n = n + 1;
right_ds = r_ar[n];
left_ds = l_ar[n];
pause(100);
print("n = %d\n", left_ds);
print("n = %d\n", right_ds);
pause(100);
high(27);
sd_mount(22, 23, 24, 25);
FILE* fp = fopen("frog.txt","a");
// Open a file for writing
fprintf(fp,"%d", left_ds); // Add contents to the file
fwrite(" ", 1, 1, fp);
pause(5);
fprintf(fp,"%d", right_ds); // Add contents to the file
fwrite("\n", 1, 1, fp);
pause(5);
fclose(fp);
pause(5); // Close the file
low(27);
pause(100);

}
pause(200);
} */

void navigate(){
float v2;
```

```
int left_deg = 0;
int right_deg = 0;
high(26);
adc_init(21, 20, 19, 18);
servo360_connect(13, 15);
servo360_connect(12, 14);
servo360_speed(13, -720);
servo360_speed(12, 720);
low(26);
while(n > 0)
{
v2 = adc_volts(1);
pause(40);
if (v2 > 2){ // sväng höger
servo360_speed(13, -720);
servo360_speed(12, 480);
}
else if (v2 < 2){ // sväng vänster
servo360_speed(13, -480);
servo360_speed(12, 720);
}
right_deg = servo360_getAngle(13);
left_deg = servo360_getAngle(12);
r_ar[n] = right_deg;
l_ar[n] = left_deg;

n = n + 1;

}
servo360_speed(12, 0);
servo360_speed(13, 0);
pause(100);
}
```