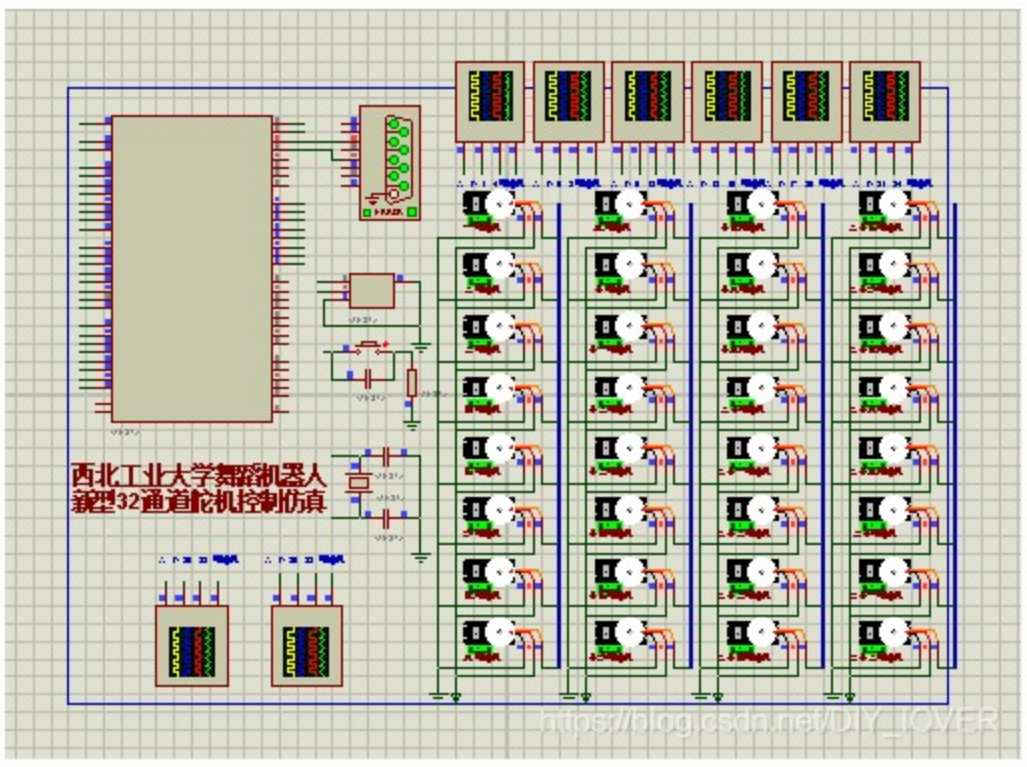
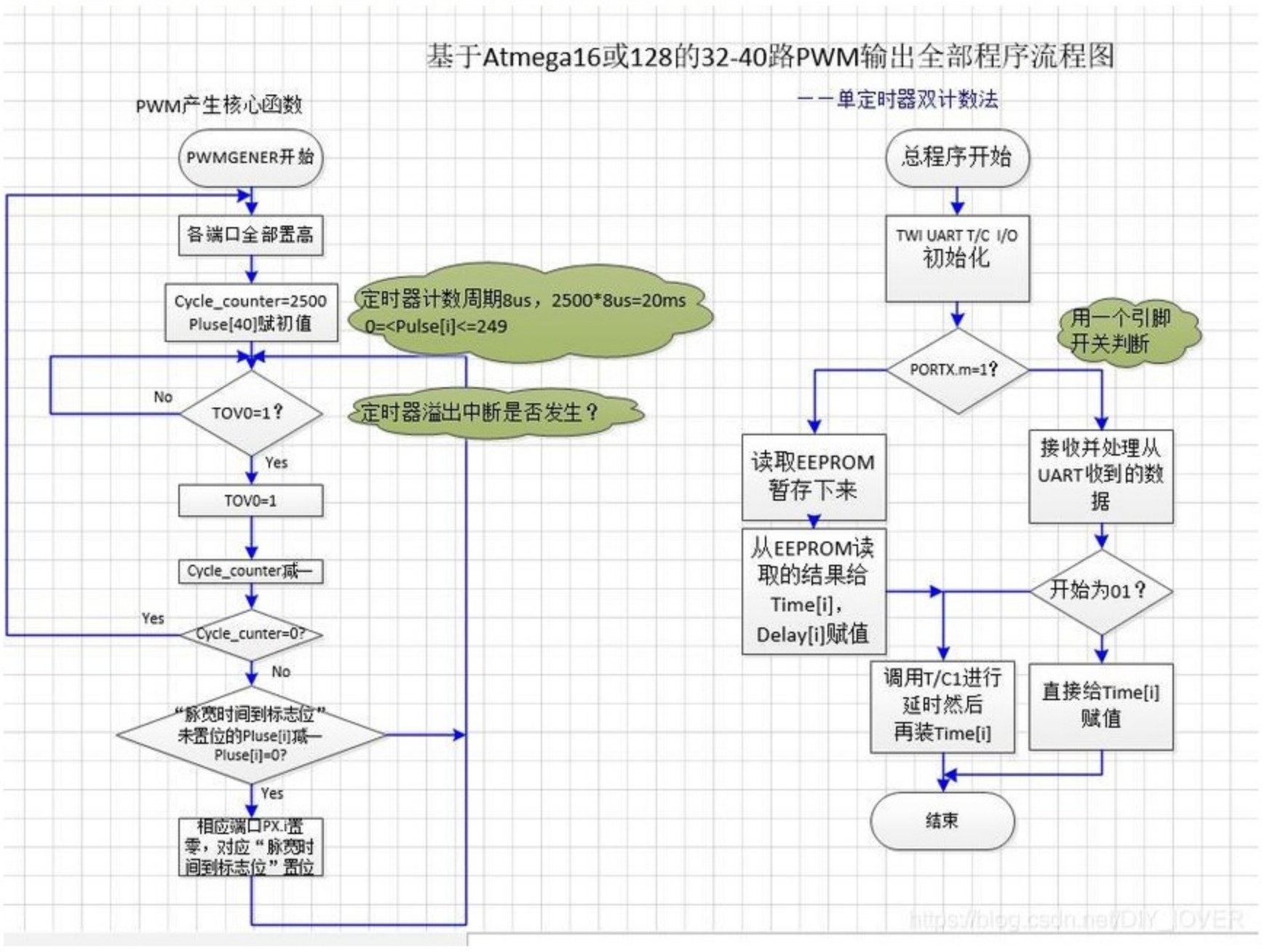
40舵机仿人机器人Proteus综合设计和仿真，包含Proteus仿真文件，Atmega8程序源文件，程序流程图

【资源下载】下载地址如下（929）：https://docs.qq.com/doc/DTlRSd01BZXNpRUxl






```
#include <mega128.h>

#define RXB8 1
#define TXB8 0
#define UPE 2
#define OVR 3
#define FE 4
#define UDRE 5
#define RXC 7

#define FRAMING_ERROR (1<<FE)
#define PARITY_ERROR (1<<UPE)
#define DATA_OVERRUN (1<<OVR)
#define DATA_REGISTER_EMPTY (1<<UDRE)
#define RX_COMPLETE (1<<RXC)

// USART1 Receiver buffer
#define RX_BUFFER_SIZE1 8
char rx_buffer1[RX_BUFFER_SIZE1];

#if RX_BUFFER_SIZE1<256
unsigned char rx_wr_index1,rx_rd_index1,rx_counter1;
#else
unsigned int rx_wr_index1,rx_rd_index1,rx_counter1;
#endif

// This flag is set on USART1 Receiver buffer overflow
bit rx_buffer_overflow1;
//新型40路PWM控制方法函数
void PWMGENERATION(void);
unsigned char Pluse[40];
unsigned int Cycle_counter=4000;


// USART1 Receiver interrupt service routine
interrupt [USART1_RXC] void usart1_rx_isr(void)
{
char status,data;
status=UCSR1A;
data=UDR1;
if ((status & (FRAMING_ERROR | PARITY_ERROR | DATA_OVERRUN))==0)
   {
   rx_buffer1[rx_wr_index1]=data;
   if (++rx_wr_index1 == RX_BUFFER_SIZE1) rx_wr_index1=0;
   if (++rx_counter1 == RX_BUFFER_SIZE1)
```