**Listing 1. Kod programu odpowiedzialny za stabilizację prędkości obrotowej**

error **=** **(**int32\_t**)(**imp\_zad **-** enk\_cnt\_copy**);**

**if(**error **>=** 0**){**abs\_error **=** **(**uint32\_t**)(**error**);}** **else** **{**abs\_error **=** **(**uint32\_t**)(-**1 **\*** error**);}**

//dla jakiejkolwiek różnicy

**if(**error **>** 0**)**

**{**

OCR1B**++;**

**if(**OCR1B **>=** tabl\_ICR1**[**f\_PWM**]){**OCR1B **=** tabl\_ICR1**[**f\_PWM**];}** //ograniczenie do nasycenia

**}**

**if(**error **<** 0**)**

**{**

OCR1B**--;**

**if(**OCR1B **>=** tabl\_ICR1**[**f\_PWM**]){**OCR1B **=** 0**;}**

**}**

//dla różnicy o 1%

**if(**error **>** 0 **&&** abs\_error **>** **(**uint32\_t**)(**imp\_zad**/**100**))**

**{**

OCR1B **+=** **(**tabl\_ICR1**[**f\_PWM**]/**100**);**

**if(**OCR1B **>=** tabl\_ICR1**[**f\_PWM**]){**OCR1B **=** tabl\_ICR1**[**f\_PWM**];}**

**}**

**if(**error **<** 0 **&&** abs\_error **>** **(**uint32\_t**)(**imp\_zad**/**100**))**

**{**

OCR1B **-=** **(**tabl\_ICR1**[**f\_PWM**]/**100**);**

**if(**OCR1B **>=** tabl\_ICR1**[**f\_PWM**]){**OCR1B **=** 0**;}**

**}**

//dla różnicy o 2%

**if(**error **>** 0 **&&** abs\_error **>** **(**uint32\_t**)(**imp\_zad**/**50**))**

**{**

OCR1B **+=** **(**tabl\_ICR1**[**f\_PWM**]/**50**);**

**if(**OCR1B **>=** tabl\_ICR1**[**f\_PWM**]){**OCR1B **=** tabl\_ICR1**[**f\_PWM**];}**

**}**

**if(**error **<** 0 **&&** abs\_error **>** **(**uint32\_t**)(**imp\_zad**/**50**))**

**{**

OCR1B **-=** **(**tabl\_ICR1**[**f\_PWM**]/**50**);**

**if(**OCR1B **>=** tabl\_ICR1**[**f\_PWM**]){**OCR1B **=** 0**;}**

**}**