```
MotorDriveInit
     //*** PWM Initialization ***//
      set PWM Chan 3&4 enabled
      set to output initially high
      set to output initially high
      select clock SA /SB
      set clk to M/8
      set CLOCKSA to 20 kHz
      set CLOCKSB to 20 kHz
      Map ports T4 & T3 to PWM chan 4 and chan 3
      set PSMPER3 and PWMPER4 equal to 128

      // make motor drive directions outputs
      set MOTOR_DRIVE_REG |= (MOTOR_LB |MOTOR_RB)


SetMotorDriveDuty(int DC, char channel)
// note that the LMD18200 motor driver was used (operates differently than
the l298n introduced in class)

   subtract 128 from DC // now 128 is full forward, -128 is full reverse
      if channel equals MOTOR_LA
            if DC < 0
               set MOTOR_LB pin high
            else
               set MOTOR_LB pin low

      if channel equals MOTOR_RA
            if DC < 0
               set MOTOR_RB pin high
            else
               set MOTOR_RB pin low

      if DC < 0, multiply by -1
      if DC is greater than 128, set DC = 128

      switch(channel)

            case MOTOR_RA:
                  set PWMDTY3 equal to DC

            case MOTOR_LA:
                  set PWMDTY4 equal to DC
```