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/*-----\
Use :
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void FCM_Main()
{
    // Name: Call Component Macro, Type: Call Component Macro: Servo_Controller1::Initialise()
    FCD_Odd21_Servo_Controller1_Initialise();

    // Name: Call Component Macro, Type: Call Component Macro: Servo_Controller1::EnableServo(0)
    FCD_Odd21_Servo_Controller1_EnableServo(0);

    // Name: Loop, Type: Loop: While 1
    while (1)
    {
        // Name: Call Component Macro, Type: Call Component Macro: ADC_in=slider_plastic1::GetByte()
        FCV_ADC_IN = FCD_Odd101_slider_plastic1_GetByte();

        // Name: Loop, Type: Loop: Loop 256 times
        for (FCLV_LOOP0=0; (FCLV_LOOP0)<(256); (FCLV_LOOP0)++)
        {
            // Name: Delay, Type: Delay: ADC_in ms
            FCI_DELAYBYTE_MS(FCV_ADC_IN);

            // Name: Call Component Macro, Type: Call Component Macro: angolo=Servo_Controller1::MoveToPosition(0, angolo)
            FCV_ANGOLO = FCD_Odd21_Servo_Controller1_MoveToPosition(0, FCV_ANGOLO);

            // Name: Calculation, Type: Calculation:
            // angolo = 0
            // angolo = angolo + 1
            FCV_ANGOLO = 0;
            FCV_ANGOLO = FCV_ANGOLO + 1;

        }

        // Name: Loop, Type: Loop: Loop 256 times
        for (FCLV_LOOP0=0; (FCLV_LOOP0)<(256); (FCLV_LOOP0)++)
        {
            // Name: Delay, Type: Delay: ADC_in ms
            FCI_DELAYBYTE_MS(FCV_ADC_IN);

            // Name: Call Component Macro, Type: Call Component Macro: angolo=Servo_Controller1::MoveToPosition(0, angolo)
            FCV_ANGOLO = FCD_Odd21_Servo_Controller1_MoveToPosition(0, FCV_ANGOLO);

            // Name: Calculation, Type: Calculation:
            // angolo = angolo - 1
            FCV_ANGOLO = FCV_ANGOLO - 1;

        }

    }

}

```