```
// FILE: xl320-helloServo1_0a.nxc - Works!
// DATE: 12/08/19 14:03
// AUTH: P.Oh
// DESC: Command servo to rotate back-and-forth by fixed amount
// VERS: 1.0a: based on P.Oh's xl320-defines1_0a.h and xl320-funtions1_0a.h
// REFS: xl320-functions1_0a.h; xl320-defines.h, xl320-helloLed1_0a.nxc
//       09/10/19 ppt-paulOhDynamixelXl320HeaderFile-1.0a.pptx
// NOTE: If factory default XL-320 used, then ID is 0x01
//       ID of 0xFE commands any and all XL-320 motors

#include "xl320-defines1_0a.h"   // XL-320 defines from Control Table
#include "xl320-functions1_0a.h" // P.Oh functions written for XL-320

#define ID_ALL_MOTORS 0XFE       // 0XFE commands all XL-320 motors
#define ID_MOTOR01    0X12       // Assumes Motor 1 configured with ID = 12

task main() {

  bool  orangeButtonPushed;      // Detect Brick Center button state
  bool  rightArrowButtonPushed;  // Detect Brick right arrow button state
  bool  leftArrowButtonPushed;   // Detect Brick left arrow button state
  bool  greyButtonPushed;        // Detect Brick Grey/Abort button state
  UseRS485();
  RS485Enable();
  // Note: First, use Dynamixel Wizard to set XL-320 to desired baud rate
  // Then, use RS485Uart to match this baud rate e.g. 57600
  RS485Uart(HS_BAUD_57600, HS_MODE_8N1); // 57600 baud, 8bit, 1stop, no parity

  ClearScreen();
  // Prompt user to begin
  TextOut(0, LCD_LINE1, "Stop: Press GRAY" );

  do {
     greyButtonPushed = ButtonPressed(BTNEXIT, FALSE);
     XL320_servo(ID_ALL_MOTORS, 900, 200); // rotate to motor position 900, speed
200
     Wait(1500);
     XL320_servo(ID_ALL_MOTORS, 0, 200);   // counter-rotate to 0 at speed 200;
     Wait(1500);
  } while(!greyButtonPushed);
  ClearScreen();

} // end main
```