

Table 8: Approach sensor detection function

```
ISR(PCINT0_vect) { //Approach vector routine
  if (!digitalRead(ebSwitchApproachPin)) { //Was it an 16E OR WB
    if (ebApproachSwitched == 0 && wbDeparted == 0) { //1st time AND REAL not FAKE
      ebSwitchApproach = 1; //Set that interrupt has been handled
      ebApproachSwitched = 1; //Set to skip 2nd pass
      bitWrite(ledSignals2, 7, HIGH); //LED on
    }
    if (wbDeparted == 1) { //FAKE not REAL
      ebSwitchApproach = 0; //Clear
      wbDeparted = 0;
      bitWrite(ledSignals2, 7, LOW); //LED off
    }
  }
  if (!digitalRead(wbSwitchApproachPin)) { // 16E OR wb
    if (wbApproachSwitched == 0 && ebDeparted == 0) { //1st time AND REAL not FAKE
      wbSwitchApproach = 1; //Set that interrupt has been handled
      wbApproachSwitched = 1; //Set to skip 2nd pass
      bitWrite(ledSignals2, 6, HIGH); //LED on
    }
    if (ebDeparted == 1) { //FAKE not REAL
      wbSwitchApproach = 0; //Clear
      ebDeparted = 0;
      bitWrite(ledSignals2, 6, LOW); //LED off
    }
  }
}
```