Driving subpart updated

* Input voltage: ≈5V
* Maximum Input Current: ≈0.22A
* Minimum output voltage: 1.384V
* Maximum output voltage: 4.096V
* Minimum Period: 0.941s
* Maximum RPM: 63.7619

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
| Speed Level | RPM | km/h | mph | Output Voltage(v) | Input Voltage (V) | Input Current (A) | Pin(W) |
| **Very fast** | 48.58 | 0.6227 | 0.3869 | 4.05 | 4.95 | 0.216 | 1.0692 |
| **Fast** | 41.27 | 0.5289 | 0.3287 | 3.4 | 4.96 | 0.192 | 0.95232 |
| **Regular** | 32.38 | 0.4150 | 0.2579 | 2.75 | 4.97 | 0.162 | 0.80514 |
| **Slow** | 23.92 | 0.3066 | 0.1905 | 2.1 | 4.98 | 0.152 | 0.75696 |
| **Very Slow** | 13.89 | 0.1780 | 0.1106 | 1.46 | 4.99 | 0.134 | 0.66866 |

The relationship between the voltage and the RPM is almost linear.

These 5 levels of moving speed are the options for the user to send, us a command to the rover. They have been made like that in order, to be, as much simplified and user friendly. Additionally, it is more convenient and straightforward as it does not require further knowledge from the user (voltages, RPM).