```
  RPM_0 = readEncoderZ(encoder0PinZ);   // Read Encoder pin Z if RPM is in "high range" (Reads for both encoders)
  RPM_1 = readEncoderZ(encoder1PinZ);   // Read Encoder pin Z if RPM is in "high range" (Reads for both encoders)
}*/

RPM_0 = readEncoderZ(encoder0PinZ);   // Read Encoder pin Z if RPM is in "high range" (Reads for both encoders)
RPM_1 = readEncoderZ(encoder1PinZ);   // Read Encoder pin Z if RPM is in "high range" (Reads for both encoders)
#if DEBUG
  Serial.print("RPM 0 =");
  Serial.print(RPM_0);
  Serial.print("......RPM 1 =");
  Serial.println(RPM_1);
#endif
//RPM_0_Last = RPM_0;
//RPM_1_Last = RPM_1;

//(insert diff code here)

throttle_in_left = throttle_in;
throttle_in_right = throttle_in;

if((controlScheme == 1) && (loopCount > 0)){
    differential(Steering, throttle_in);
}

int leftSpeed  = map(throttle_in_left, minThrottle, maxThrottle, 0, 1023);
int rightSpeed = map(throttle_in_right, minThrottle, maxThrottle, 0, 1023);

if( leftSpeed < 5 ){  // Error checking code to ensure we do not have throttle spikes at the extremities
  leftSpeed = 0;
}
if ( leftSpeed > 1023 ){
  leftSpeed = 1023;
}
if ( rightSpeed < 5 ){
  rightSpeed = 0;
}
if( rightSpeed > 1023 ){
  rightSpeed = 1023;
}

analogWriteResolution(Res);
analogWrite(leftMotor, leftSpeed);
delay(ADC_DELAY/5);
analogWriteResolution(Res);
analogWrite(rightMotor, rightSpeed);
delay(ADC_DELAY/5);

    #if DEBUG
      #if SPEED
      Serial.print("Left Motor Voltage ");                    //Debug Statements ~ visual data
      Serial.println(leftSpeed);
      Serial.print("Right Motor Voltage");
      Serial.println(rightSpeed);
      #endif
    #endif

loopEnd = millis();
loopCount = loopCount + 1;
delayMicroseconds(5);
}
```