```
//*************************************************************************************************
//*************************************************************************************************


void setup() {
  // Setup encoder inputs
  pinMode (encoder0PinA,INPUT);
  pinMode (encoder0PinB,INPUT);
  pinMode (encoder0PinZ,INPUT);
  pinMode (encoder1PinA,INPUT);
  pinMode (encoder1PinB,INPUT);
  pinMode (encoder1PinZ,INPUT);
  pinMode (LEDPwr, OUTPUT);
  digitalWrite(LEDPwr, HIGH);
  Serial.begin (9600); // Start serial output for debugging
  loopCount = 0;
  calibrateThrottle();
  calibrateSteering();
}

/*************************************************************************************************
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 *!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!! MAIN LOOP STARTS HERE!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!!
 * /\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/\/
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 *************************************************************************************************/


void loop() {

  loopStart = millis();
  //packVoltage();  //Check the battery pack to see if it is within safe operating voltage
 // This section of the code uses the throttle code by Dakota to drive the cart from the throttle potentiometer

  analogReadResolution(Res);
  int throttle_in = analogRead(throttlePin);
  delay(ADC_DELAY);   // Delays after analogRead to allow capacitors to charge and cancels cross talk between reads
  throttle_in = analogRead(throttlePin);

  analogReadResolution(Res);
  int Steering = analogRead(steeringPin);
  delay(ADC_DELAY);
  Steering = analogRead(steeringPin);

    #if DEBUG
      #if USER_INPUT
      Serial.print("Gas: ");                              //Debug Statements ~ visual data
      Serial.println(throttle_in);
      Serial.print("Steering");
      Serial.println(Steering);
      #endif
    #endif

  /*if ((RPM_0_Last < maxRPM) || (RPM_1_Last < maxRPM)){
    RPM_0 = readEncoderAB(encoder0PinA, encoder0PinB);  //This function has no output because it changes global variables within the function.
                          // Read Encoder pins A and B if RPM is in "low range" (Reads for both encoders)
    RPM_1 = readEncoderAB(encoder1PinA, encoder1PinB);  //This function has no output because it changes global variables within the function.
                          // Read Encoder pins A and B if RPM is in "low range" (Reads for both encoders)
  } else {
```