```
RPM_0 = readEncoderZ(encoderOPinZ); // Read Encoder pin Z if RPM is in "high range" (Reads for both encoders)
465
           RPM_1 = readEncoderZ(encoder1PinZ); // Read Encoder pin Z if RPM is in "high range" (Reads for both encoders)
466
467
         1*/
468
469
         RPM_0 = readEncoderZ(encoderOPinZ);
                                              // Read Encoder pin Z if RPM is in "high range" (Reads for both encoders)
470
         RPM_1 = readEncoder2(encoder1Pin2); // Read Encoder pin Z if RPM is in "high range" (Reads for both encoders)
     #if DEBUG
471
           Serial.print("RPM 0 =");
472
473
           Serial.print(RPM_0);
           Serial.print(".....RPM 1 =");
474
475
           Serial.println(RPM_1);
476
        #endif
477
         //RPM 0 Last = RPM 0;
478
         //RPM_1_Last = RPM_1;
479
         //(insert diff code here)
480
481
         throttle_in_left = throttle_in;
482
         throttle_in_right = throttle_in;
483
484
485
         if((controlScheme == 1) && (loopCount > 0)){
             differential(Steering, throttle_in);
486
487
488
489
         int leftSpeed = map(throttle in left, minThrottle, maxThrottle, 0, 1023);
         int rightSpeed = map(throttle_in_right, minThrottle, maxThrottle, 0, 1023);
490
491
492
        if( leftSpeed < 5 ){ // Error checking code to ensure we do not have throttle spikes at the extremities
493
           leftSpeed = 0;
494
         }
495
     if ( leftSpeed > 1023 ) {
496
           leftSpeed = 1023;
497
         }
498
        if ( rightSpeed < 5 ) {</pre>
           rightSpeed = 0;
499
500
         3
     if( rightSpeed > 1023 ) {
501
502
           rightSpeed = 1023;
503
         3
504
         analogWriteResolution(Res);
505
506
         analogWrite(leftMotor, leftSpeed);
         delay(ADC DELAY/5);
507
508
         analogWriteResolution(Res);
509
         analogWrite(rightMotor, rightSpeed);
510
         delay(ADC_DELAY/5);
511
             #if DEBUG
512
513
               #if SPEED
514
               Serial.print("Left Motor Voltage ");
                                                                   //Debug Statements ~ visual data
               Serial.println(leftSpeed);
515
               Serial.print("Right Motor Voltage");
516
517
               Serial.println(rightSpeed);
518
               #endif
519
             #endif
520
         loopEnd = millis();
521
         loopCount = loopCount + 1;
522
         delayMicroseconds(5);
523
524
```