**Vision**

* Vision Sensor - Detects colors. Can be used for pathfinding to mobile goals.
* Optical Sensor - Detects the color of an object.
* GPS Sensor - Detects the robot's location. Can be used to make a robot move to exact coordinates on the field.
* Ultrasonic Range Finder - Measures distance of an object in front of it.
* Distance Sensor - Measures the distance the robot is to an object.
* Line Tracker - Detects a black or white line. Can be used to follow tape on the field.

**Position**

* Inertia Sensor - Measures acceleration of the robot's position & rotation.
* Potentiometer - Measures the rotation of a part relative to its starting position
* Rotation Sensor - Measures the rotation of a part. Can be used for setting rotation limits to arms.
* Limit Switch - Like a lever that sends a signal when triggered. Can be used to detect if an arm has reached its rotation limit.
* Bumper Switch - Like a button that sends a signal when triggered. Can be used to detect if the robot hits a wall or if an arm has reached its rotation limit.

**Sensors Needed**

* ~~(1) Vision Sensor - Locate mobile goals and move to it during autonomous period.~~
* ~~(1) Ultrasonic Range Finder - Detect if the robot is close enough to a mobile goal to pick it up during autonomous period.~~
* (1) Inertia Sensor - Make the robot rotate precisely.
* (1) Rotation Sensor- Set rotation limits to arms.
* (1) GPS Sensor - Accurately head to alliance region to drop mobile goal during autonomous period.