```
from machine import Pin, I2C, Timer
from board import *
from bno055 import BNO055 # IMU

from drv8833 import DRV8833 # your implementation
from motor import PIDMotor # your implementation, make sure this is named right!
from encoder import Encoder # your implementation, don't forget clear_count
from balance import Balance

import gc # for garbage collection methods

# Setup motors
########## Check Pin Numbers! ##########
# Change pin numbers here to match yours or rewire your robot
leftEnc = Encoder(34, 39, 2)
leftM = DRV8833(19, 16)

rightEnc = Encoder(36, 4, 1)
rightM = DRV8833(17, 21)
########## Check Pin Numbers! ##########

###### If these don't work, choose your best PI values from the previous lab #####
# Feel free to experiment
mp = 0.045
mi = 0.5
###### If these don't work, choose your best PI values from the previous lab #####

# Balancing PI constants
bp = 219
bi = 45

# setup closed loop motor controllers
pidL = PIDMotor(leftM, leftEnc)
pidR = PIDMotor(rightM, rightEnc)

# setup IMU
i2c = I2C(0, sda=23, scl=22, freq=12500)
imu = BNO055(i2c)

# status LED
led = Pin(LED, mode=Pin.OUT)

dt = 0.02
ticks = 0
sec = 0
old_sec = 0
loopReady = False
```