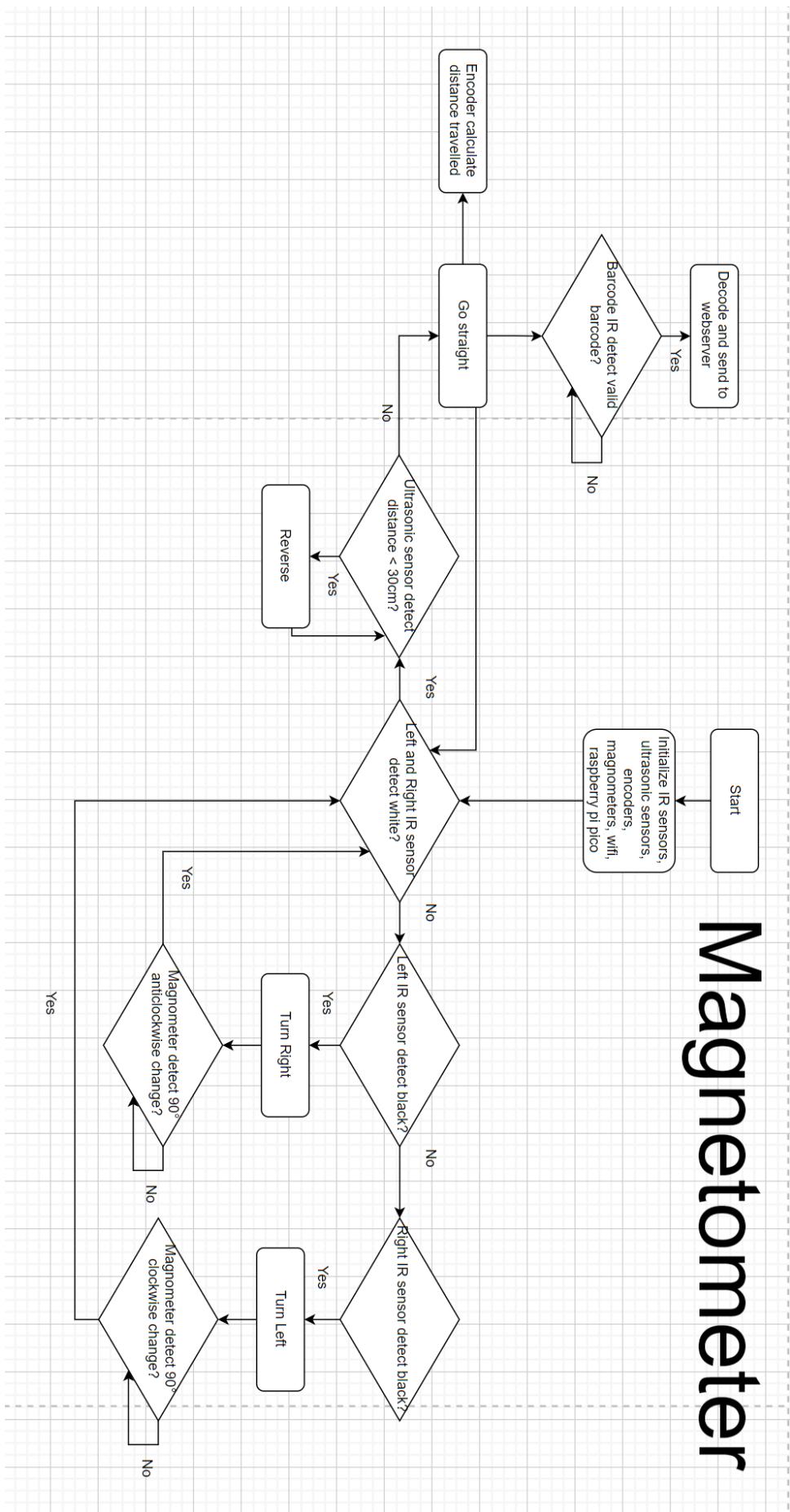
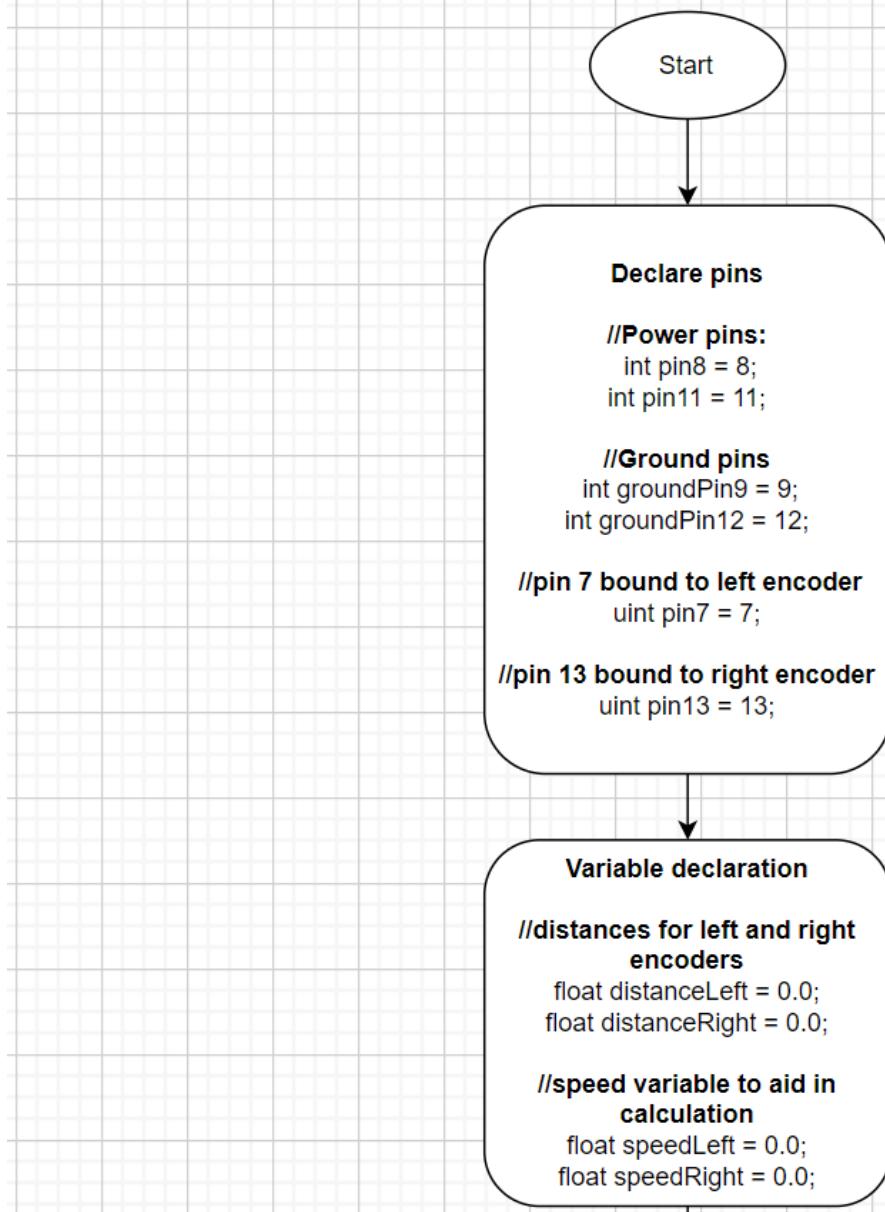


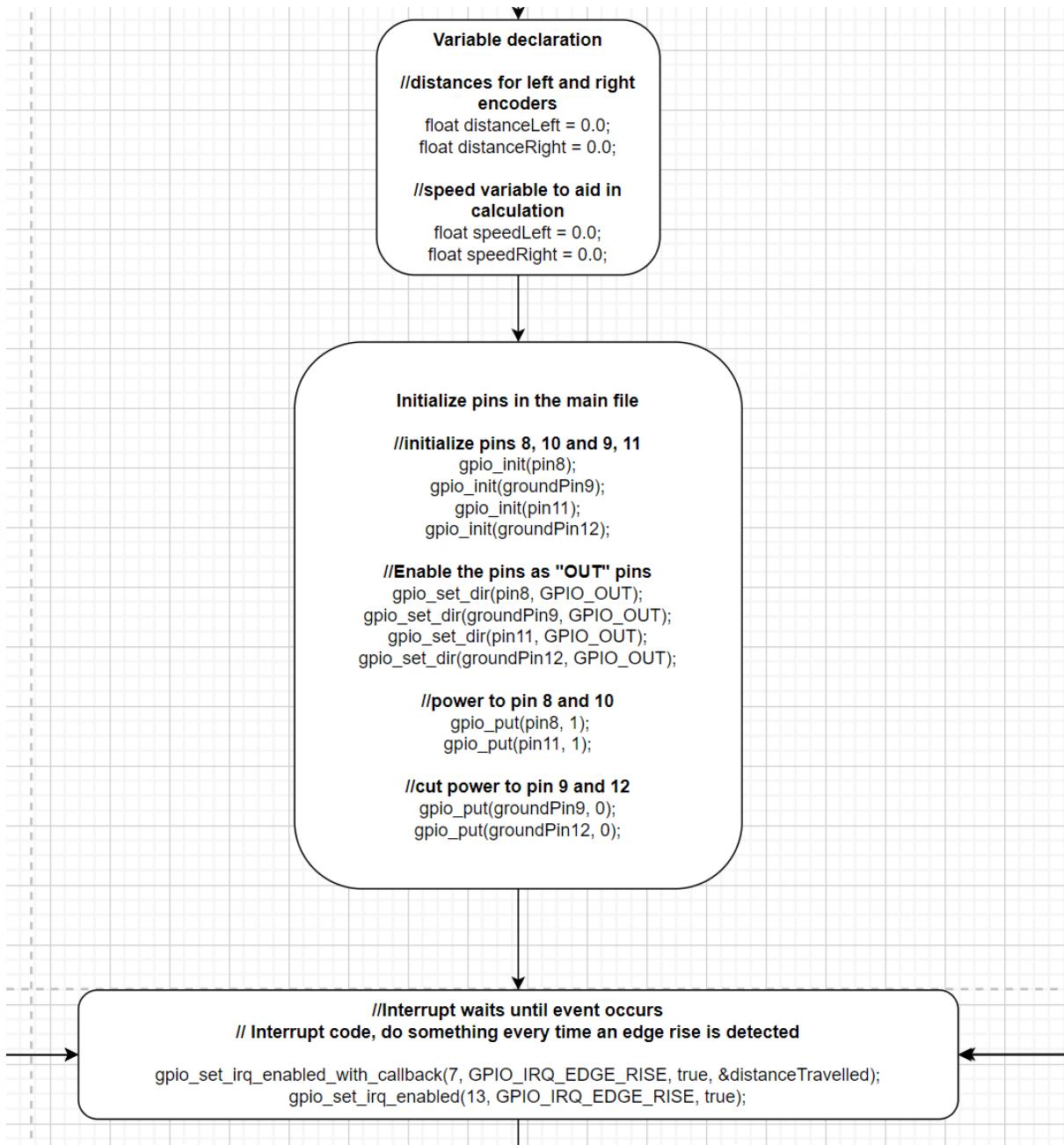
Magnetometer



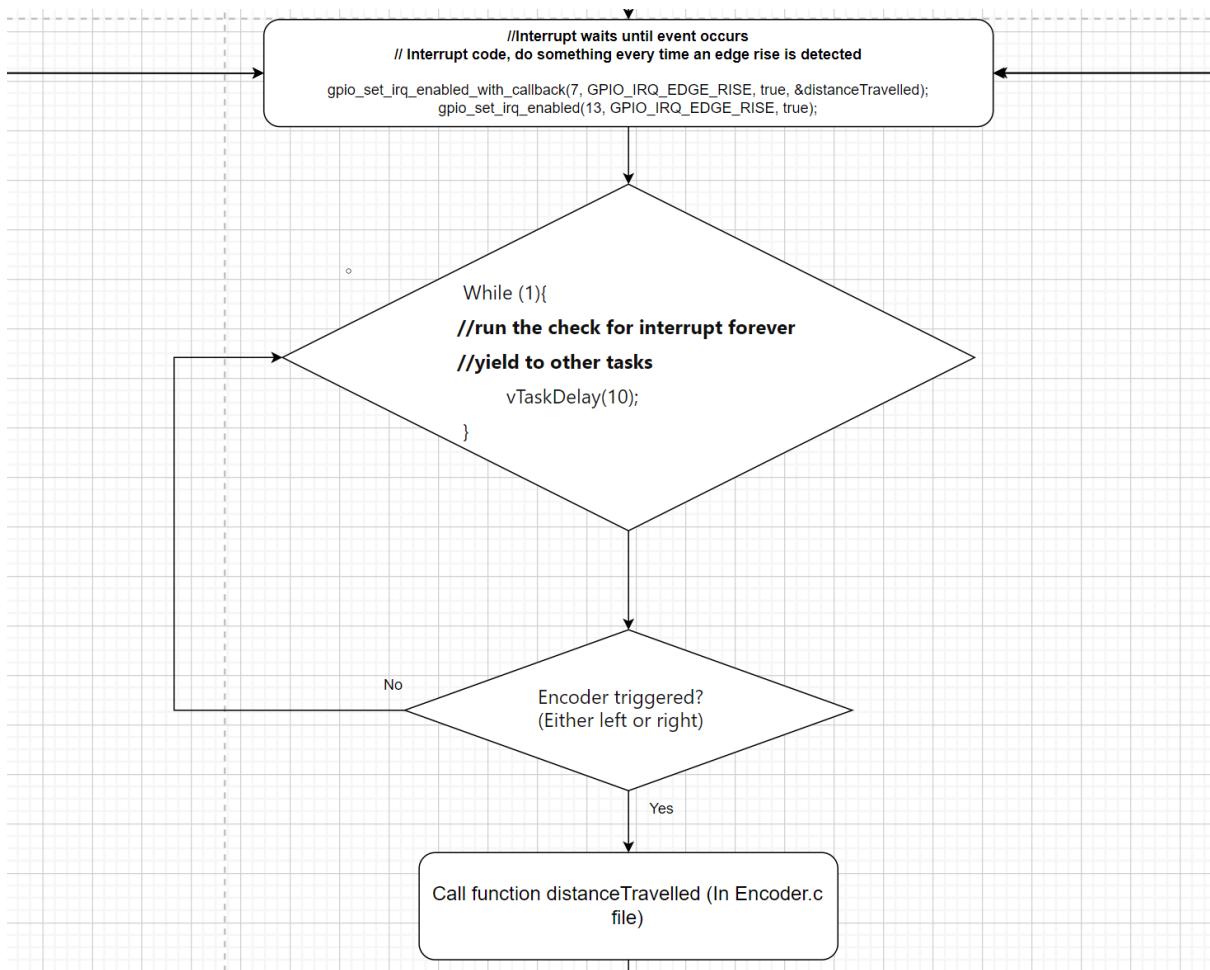
Encoder

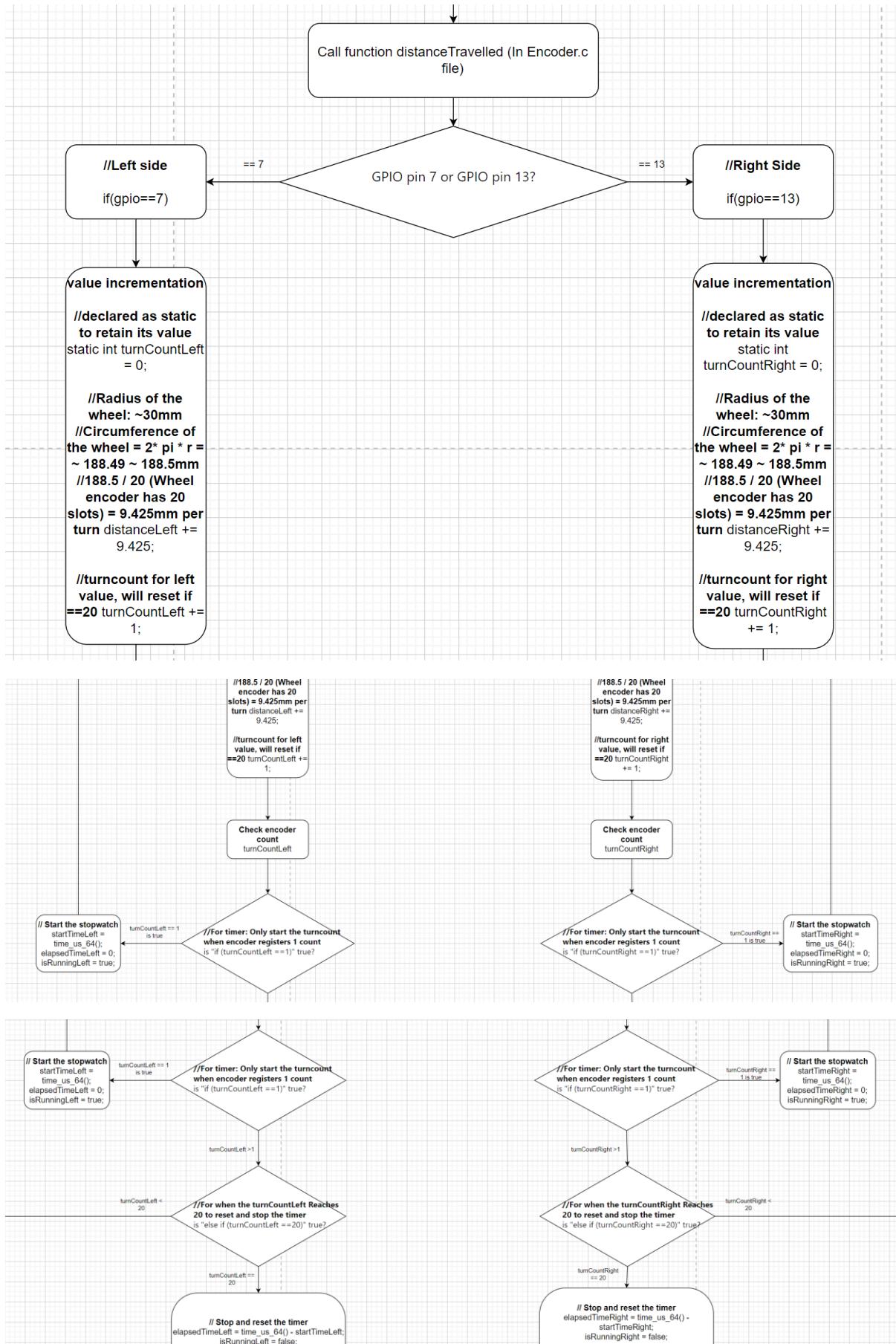
Encoder

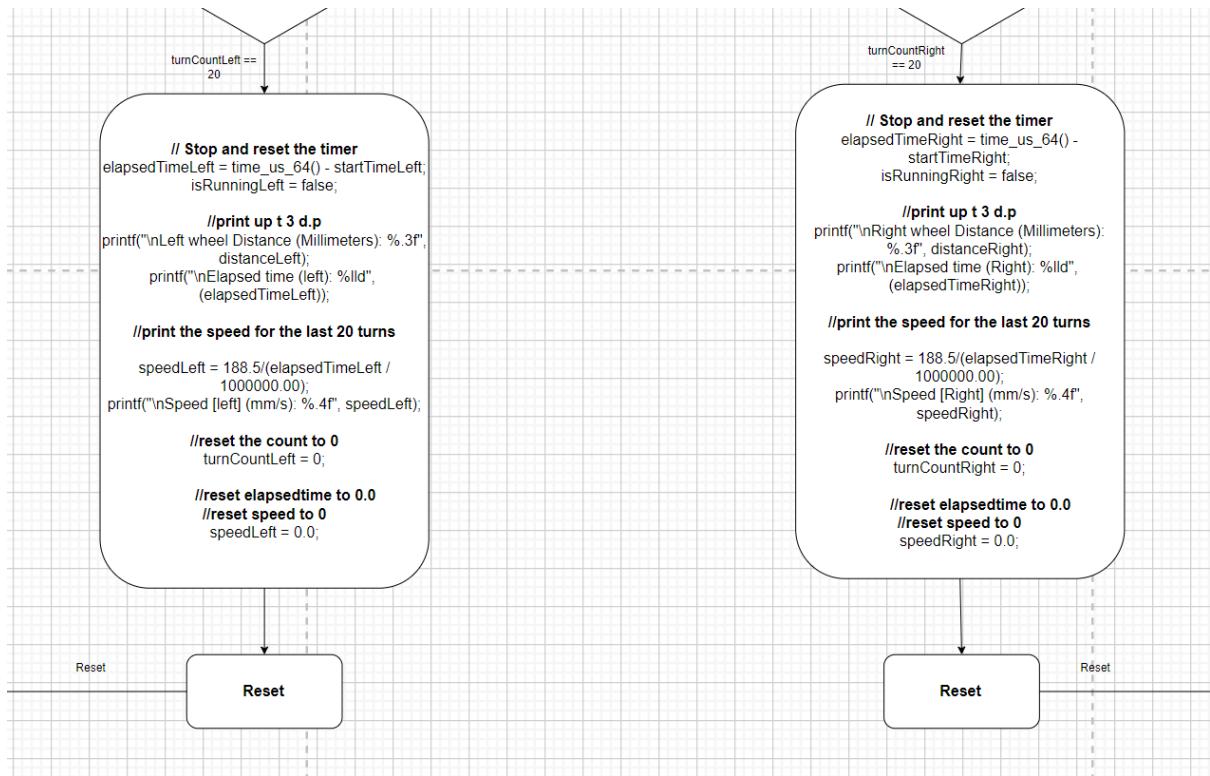




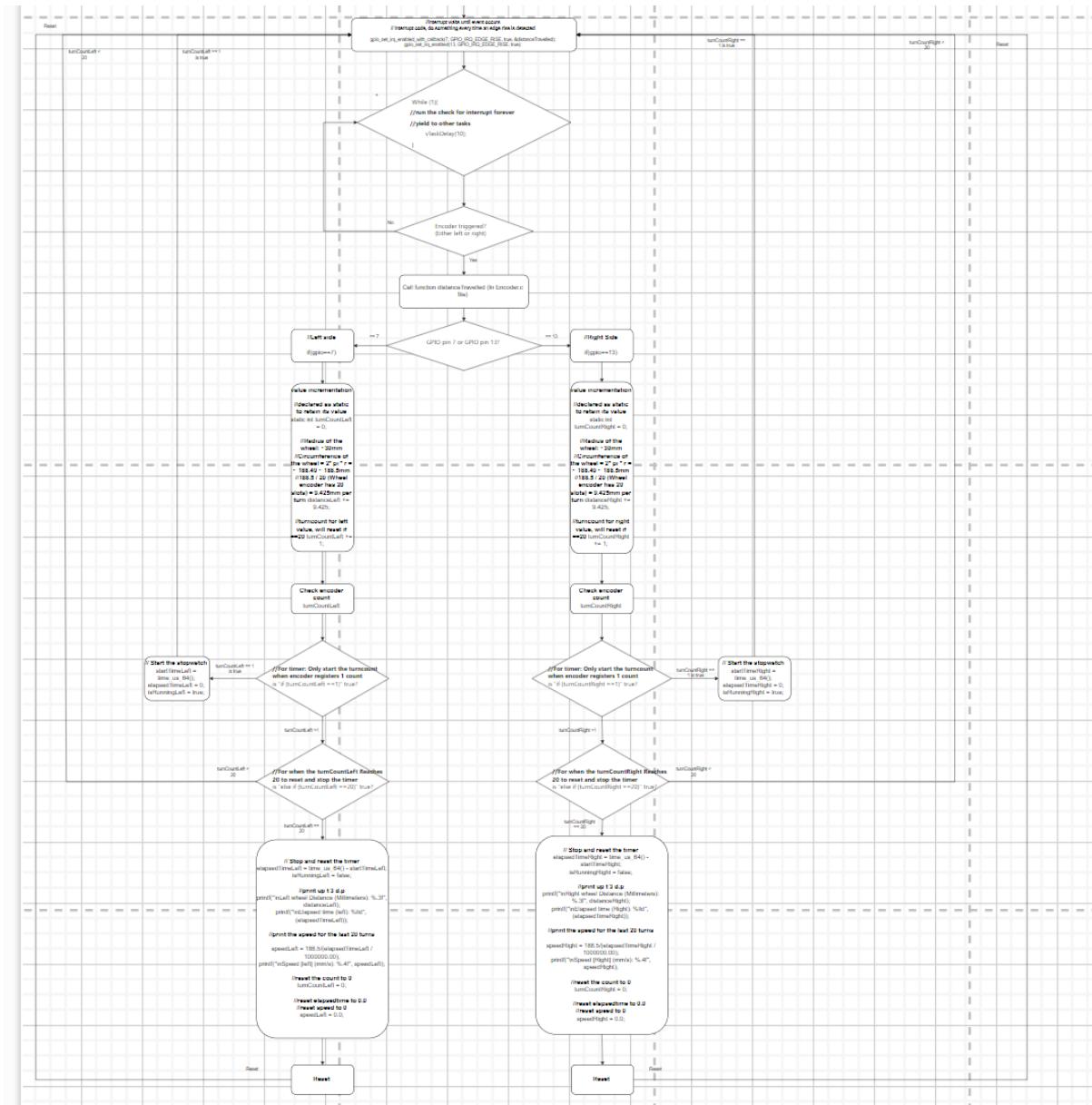
Encoder – main logic loop



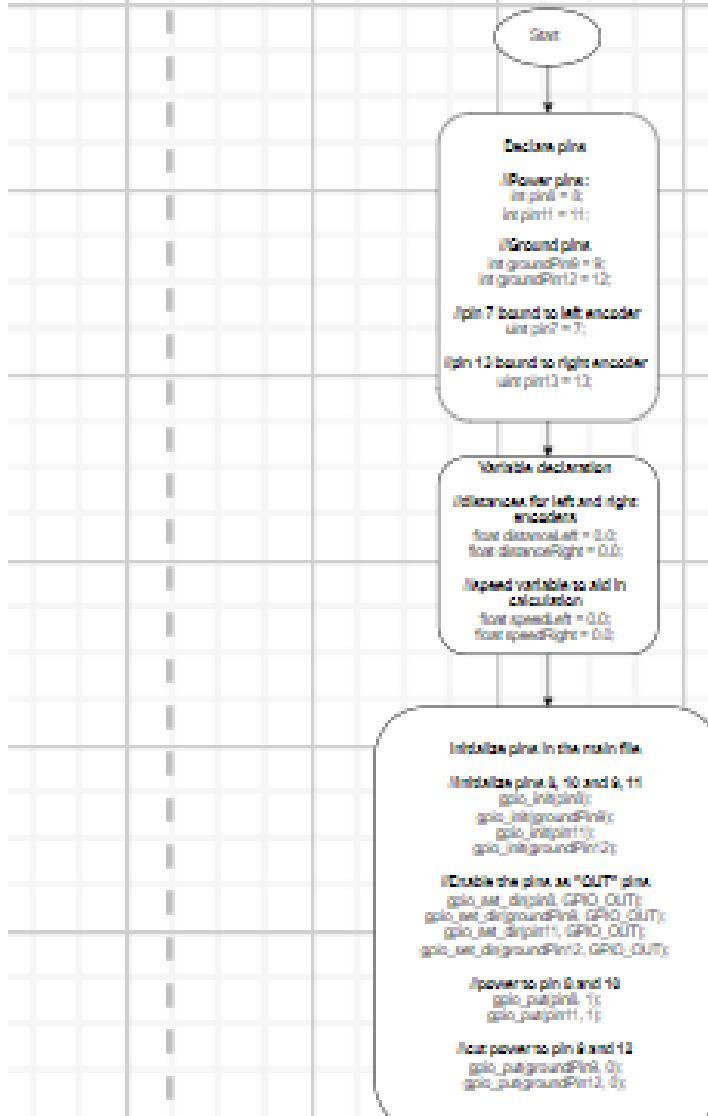


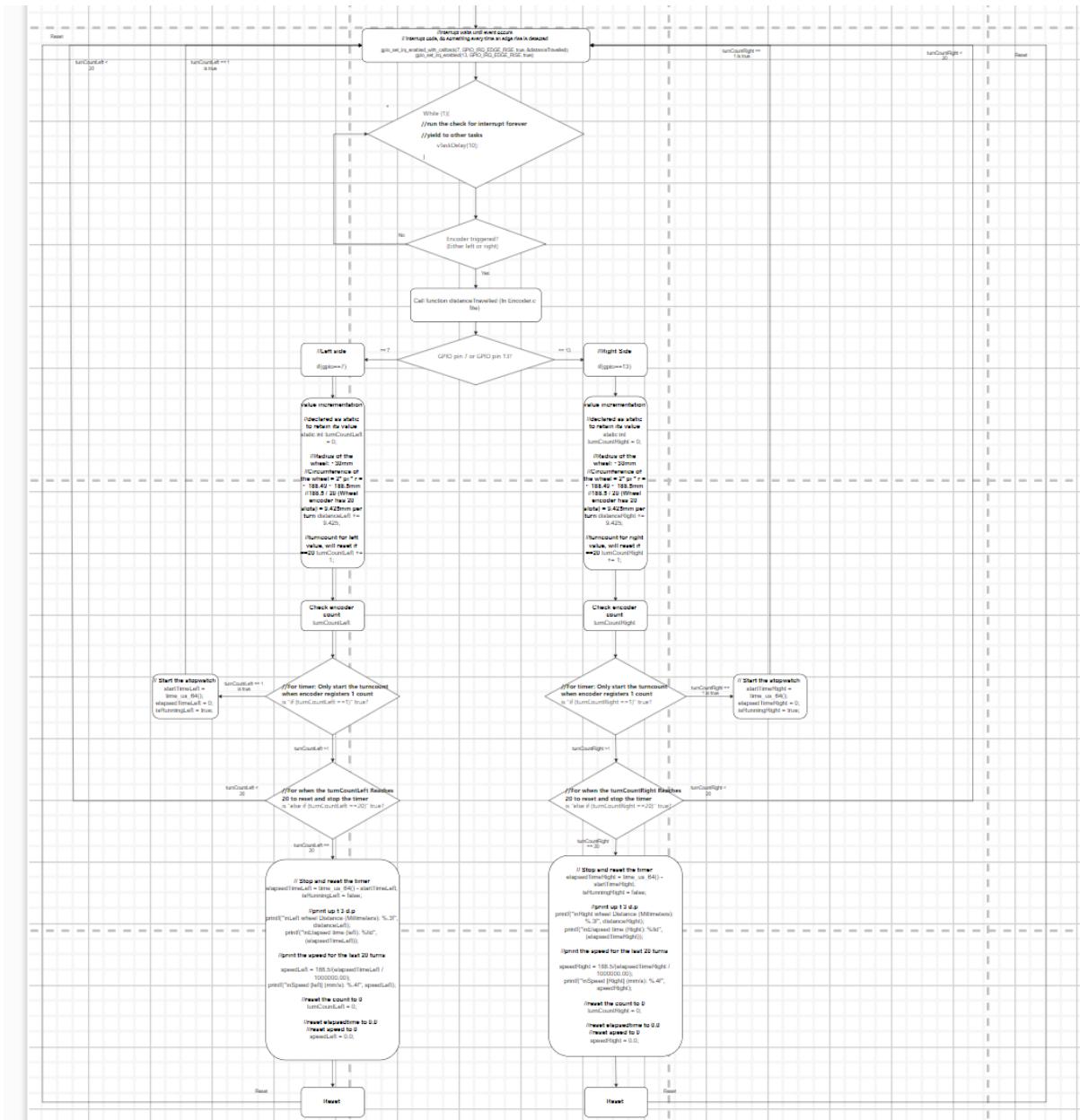


Encoder – Showing feedback into interrupt function.

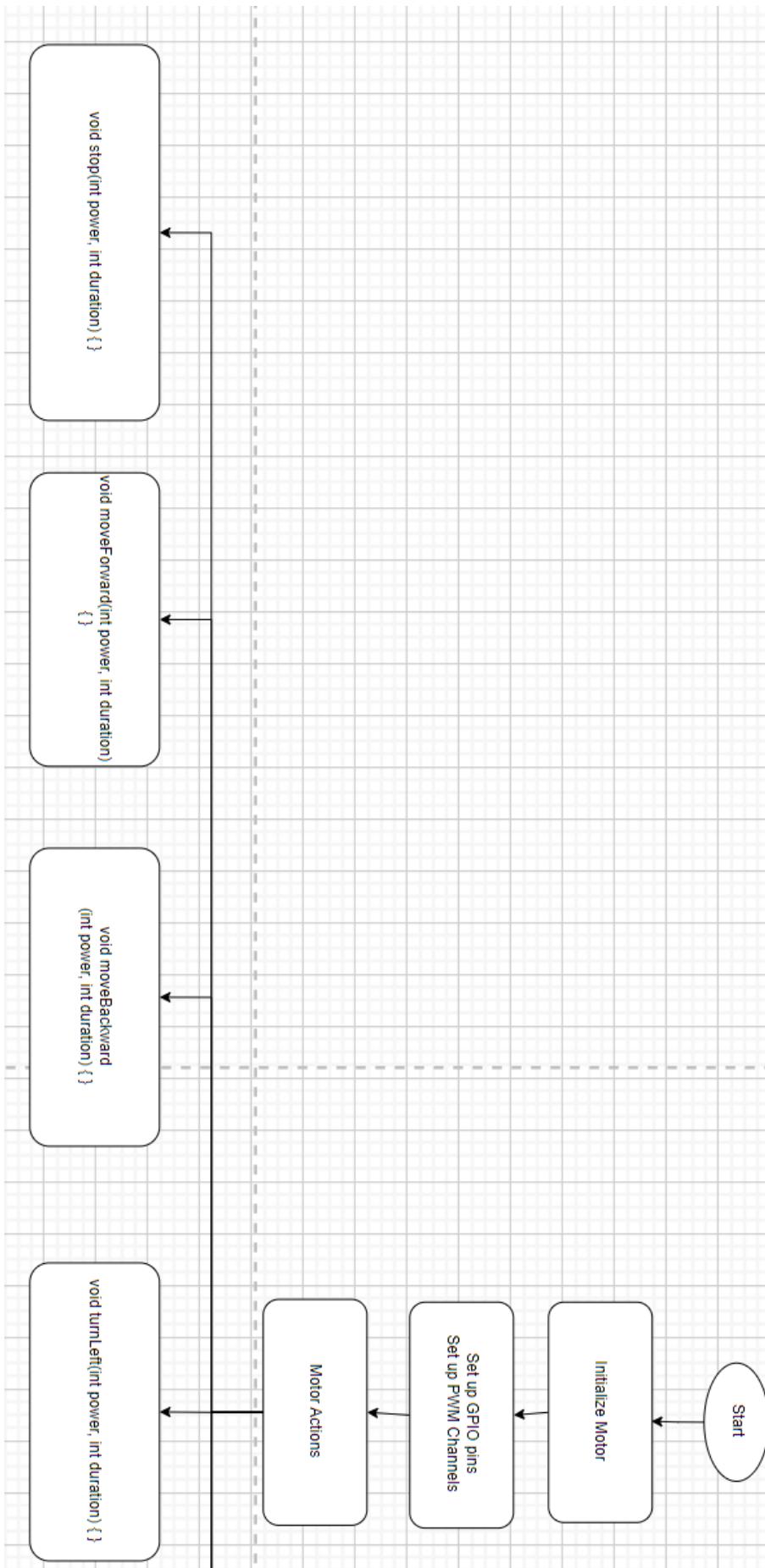


Encoder





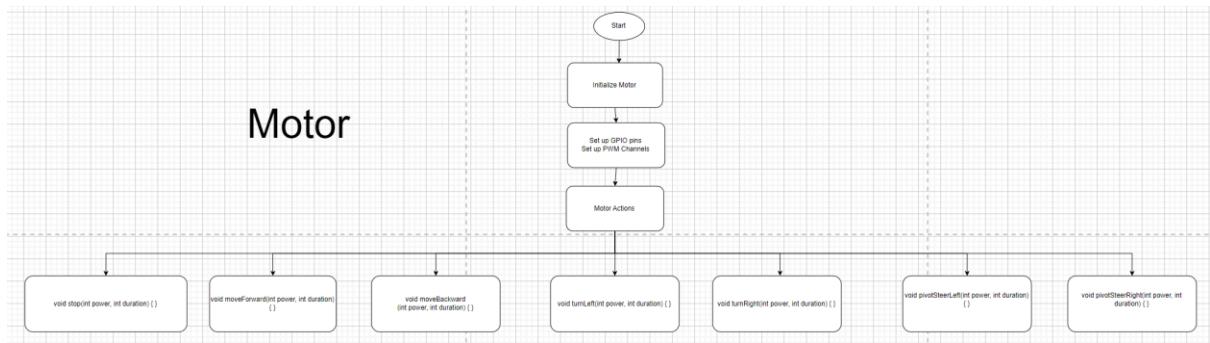
Motor – function call logic



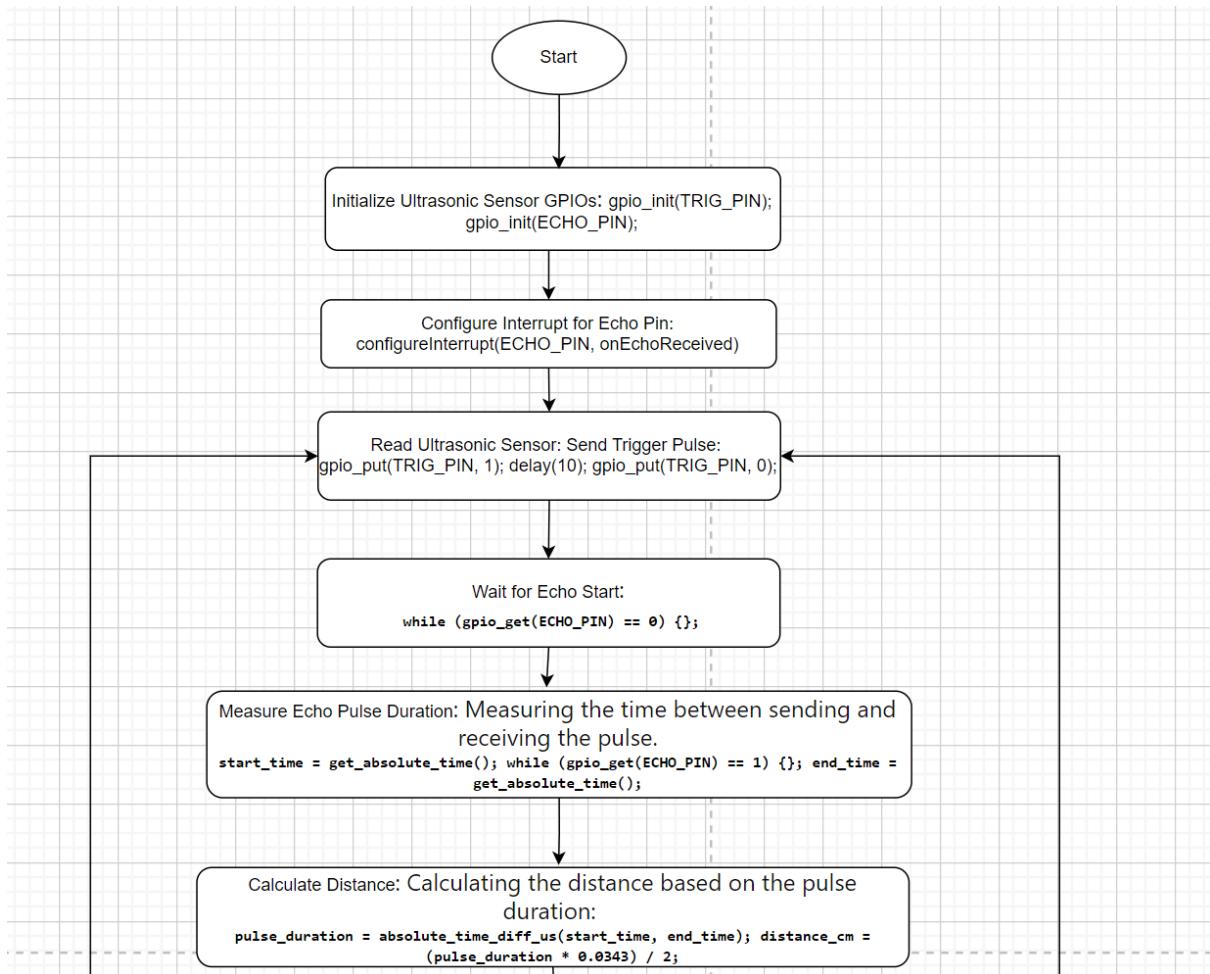
```
void turnRight(int power, int duration) {}
```

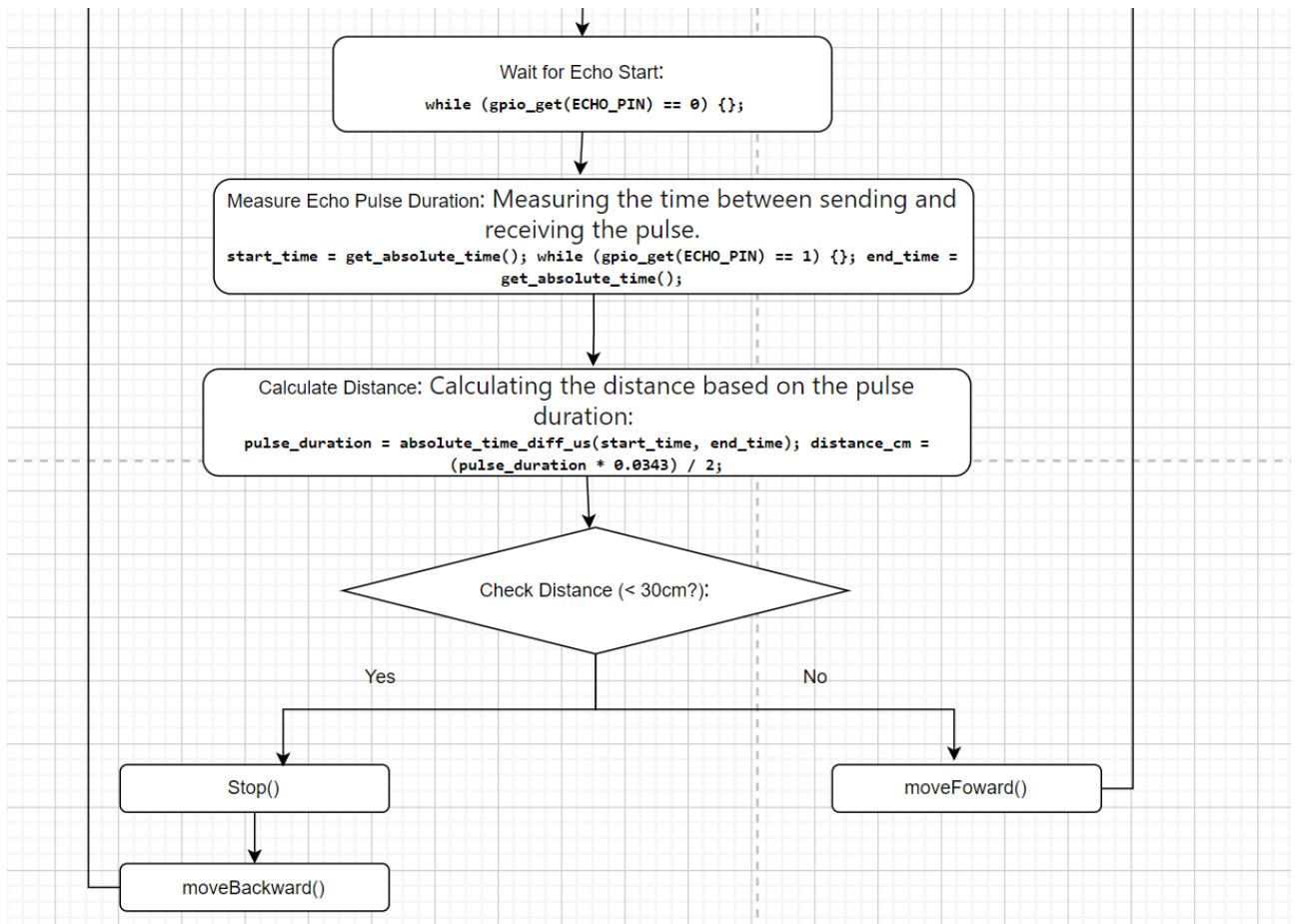
```
void pivotSteerLeft(int power, int duration)  
{ }
```

```
void pivotSteerRight(int power, int  
duration) {}
```

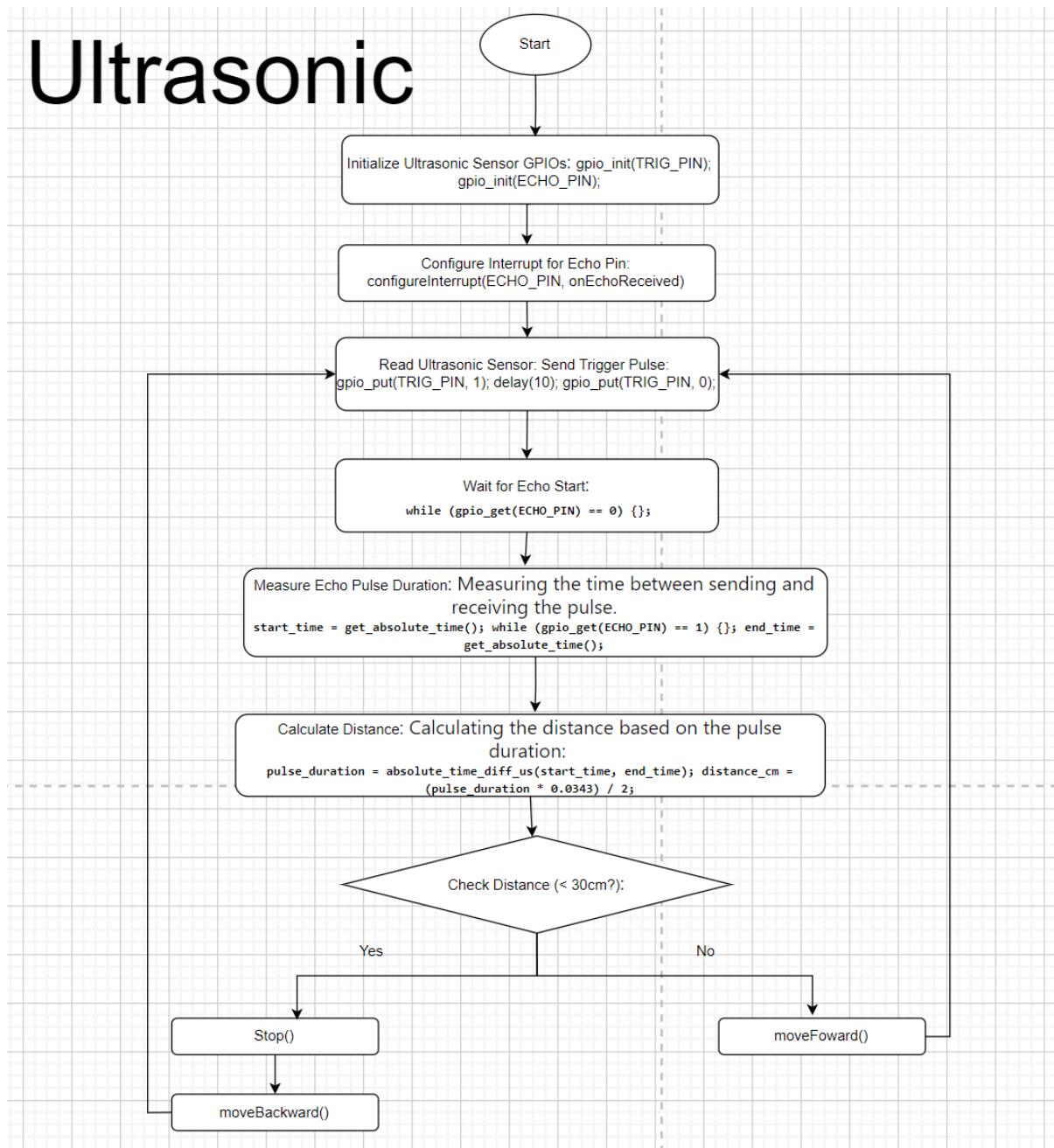


Ultrasonic



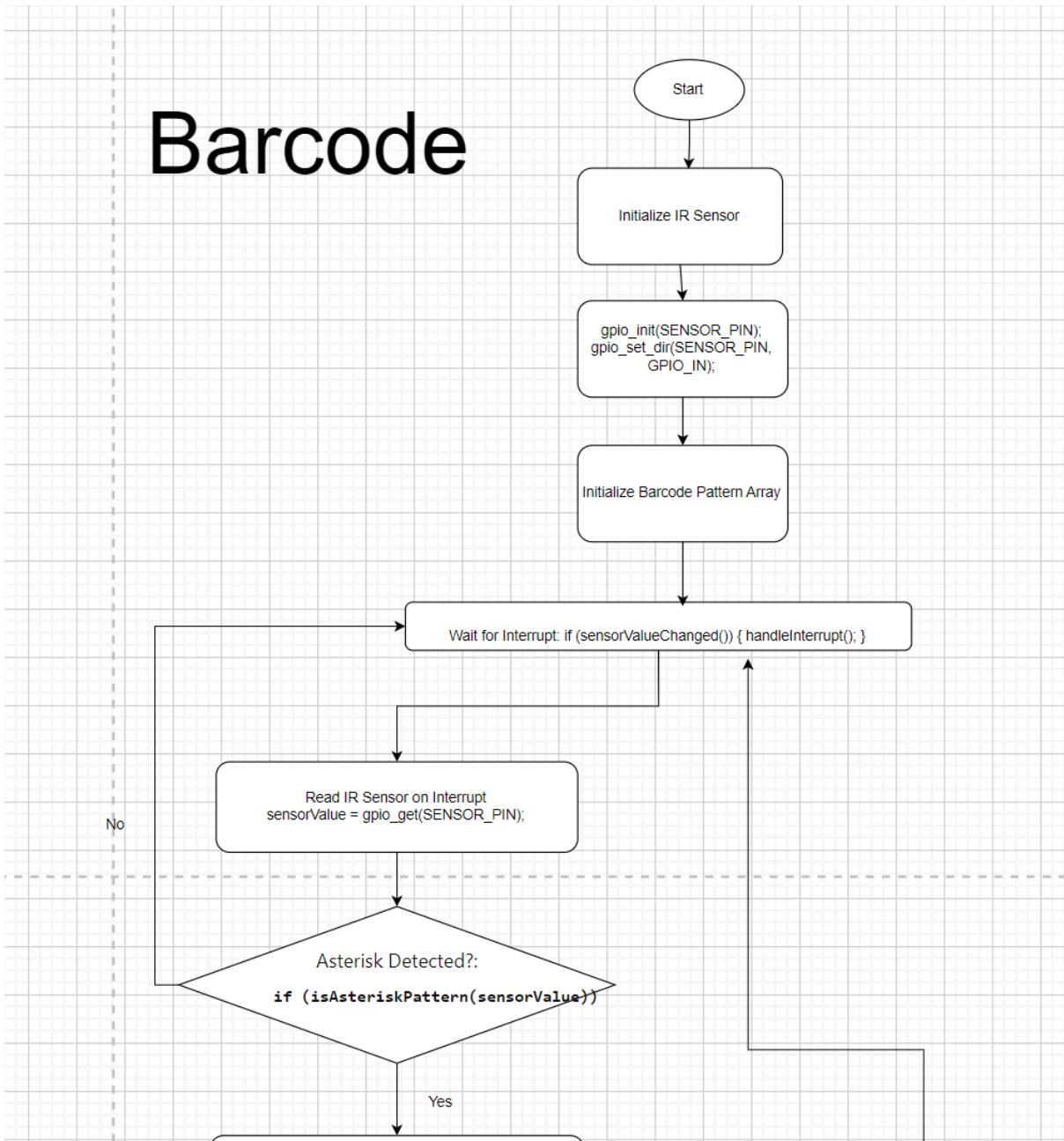


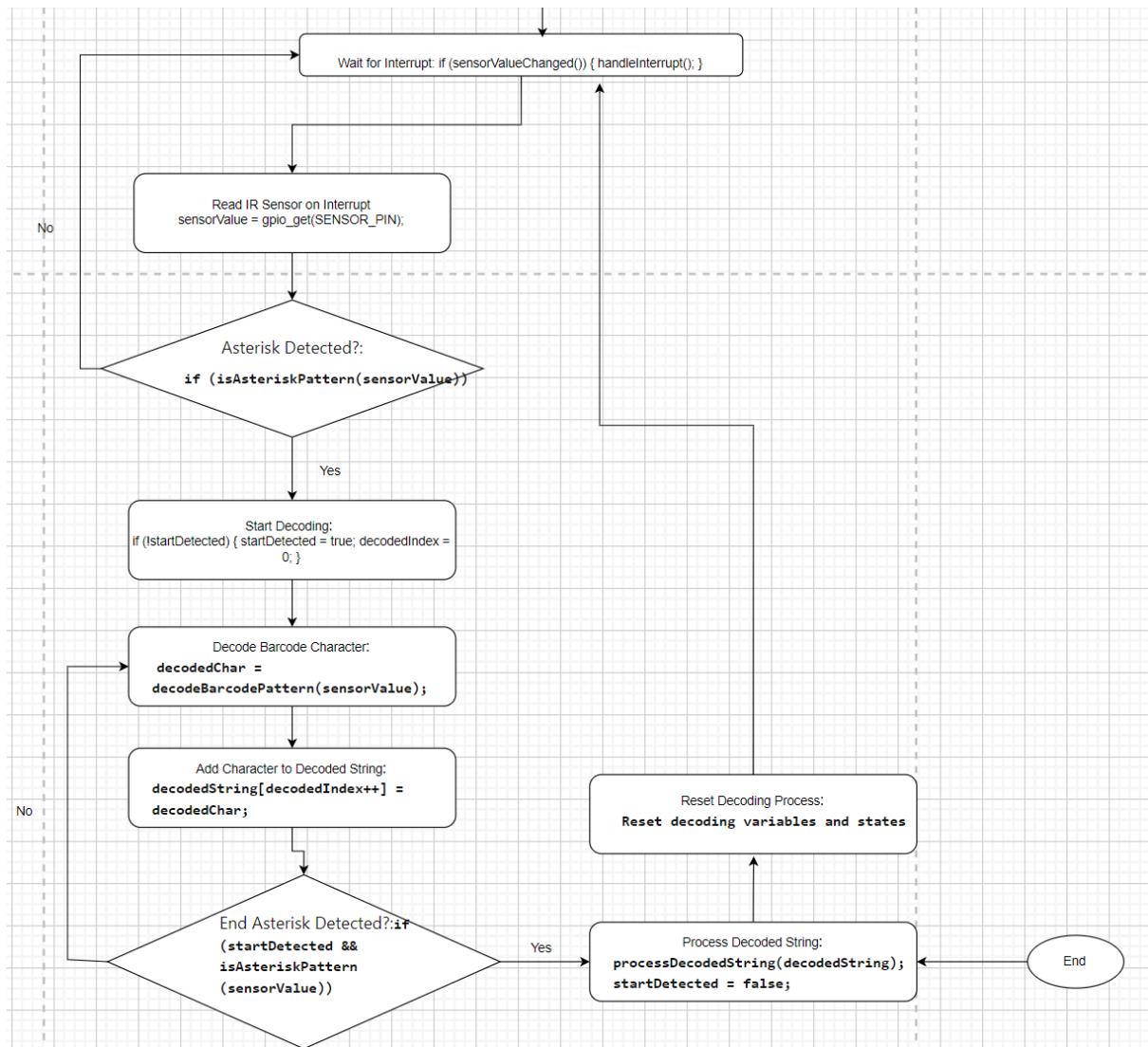
Ultrasonic



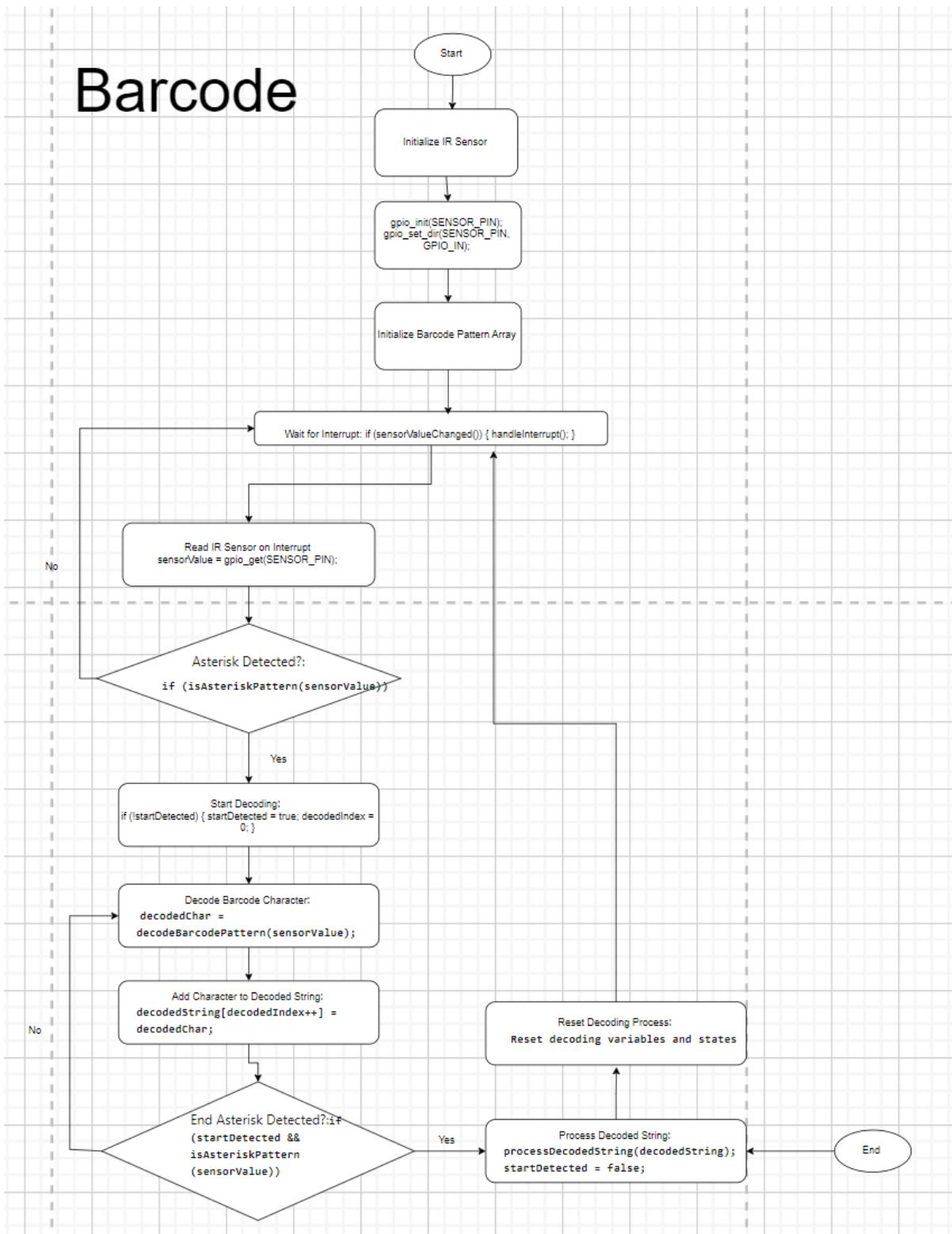
Barcode

Barcode



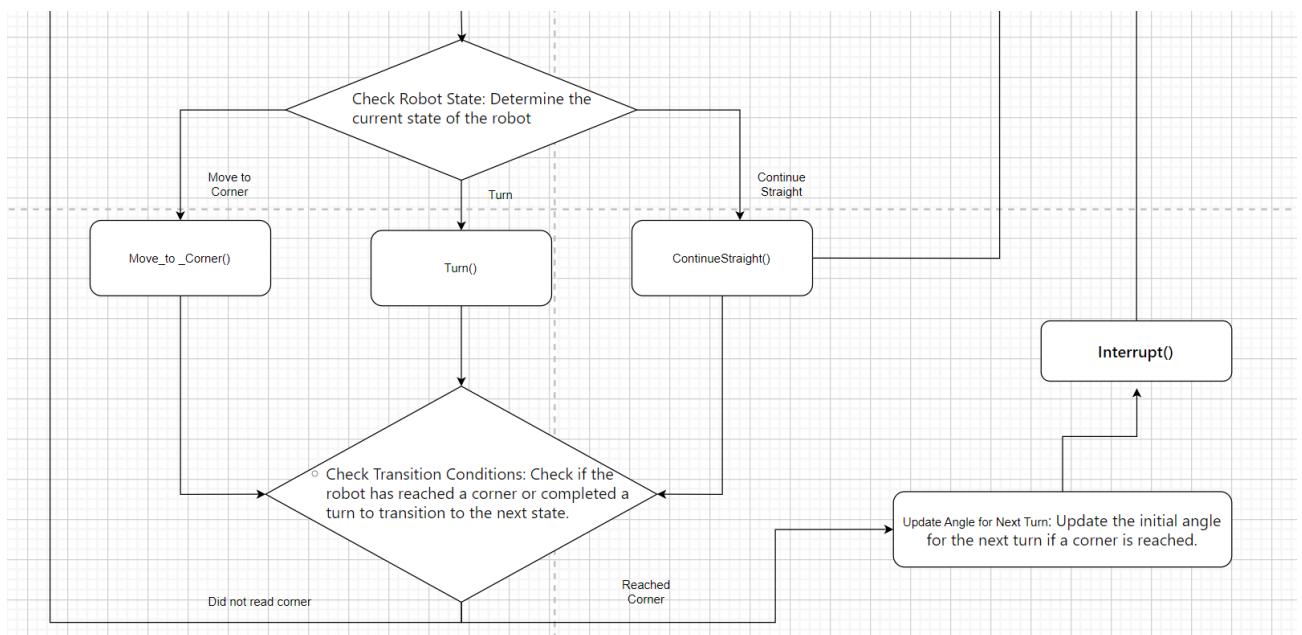
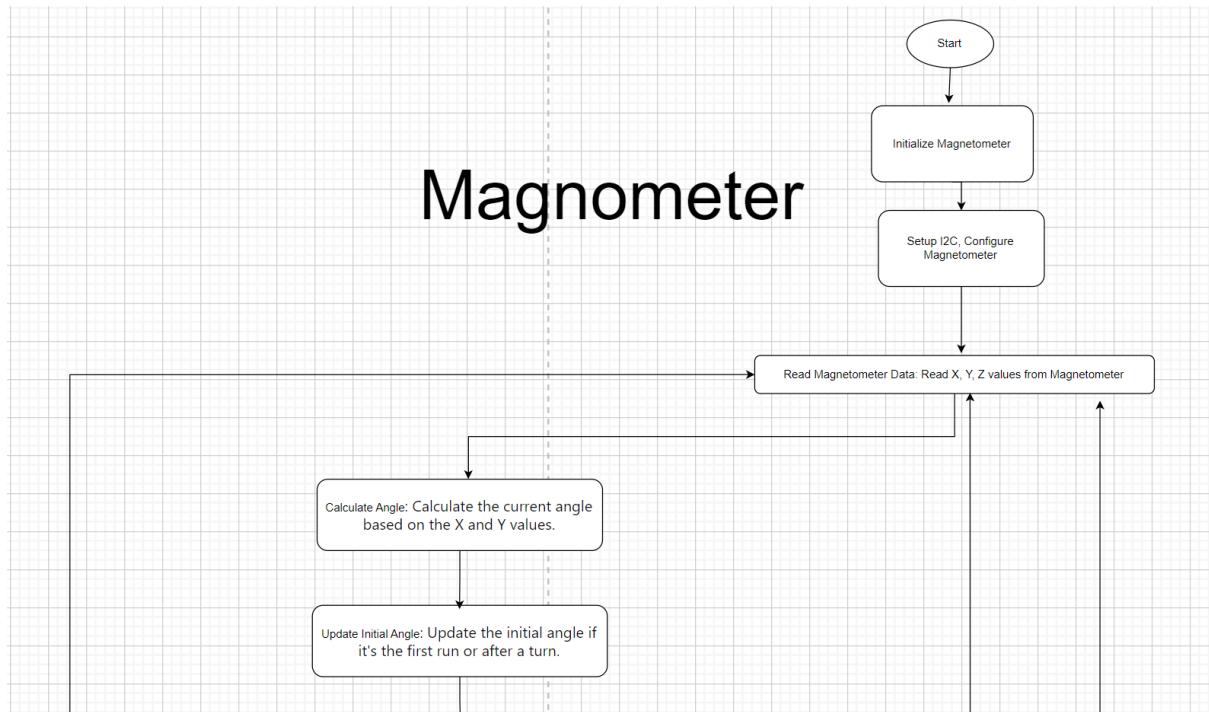


Barcode

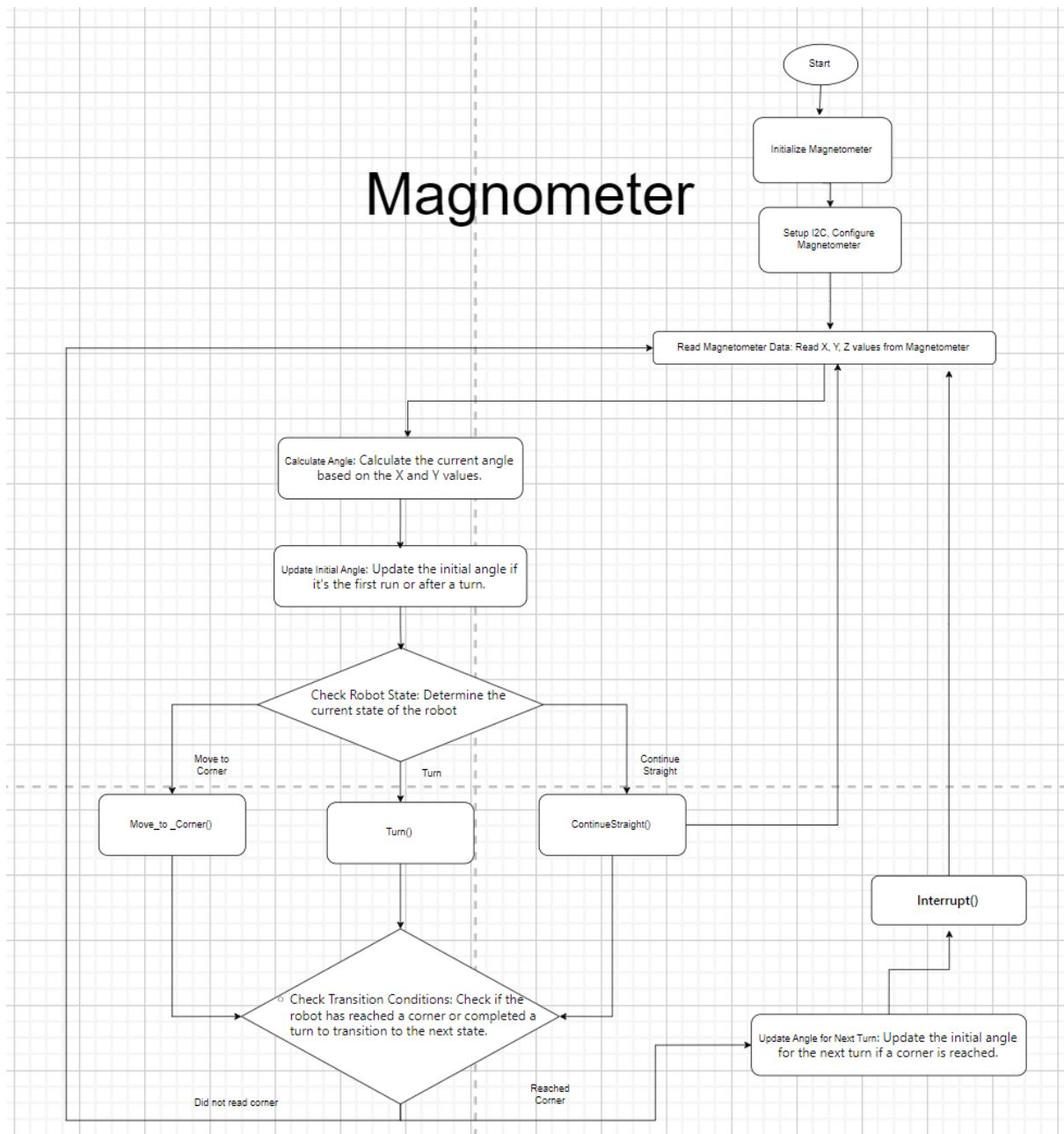


Magnometer

Magnometer

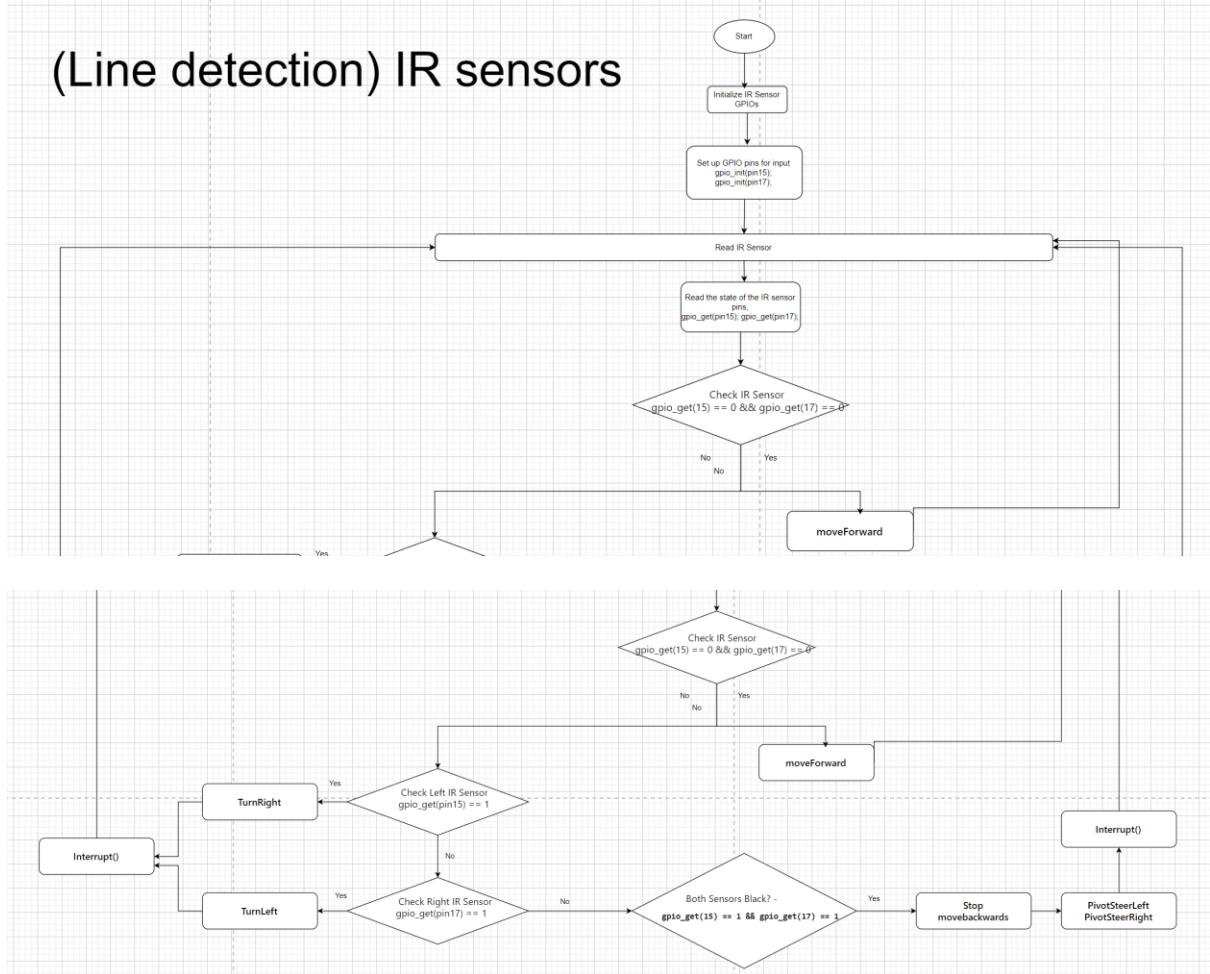


Magnometer

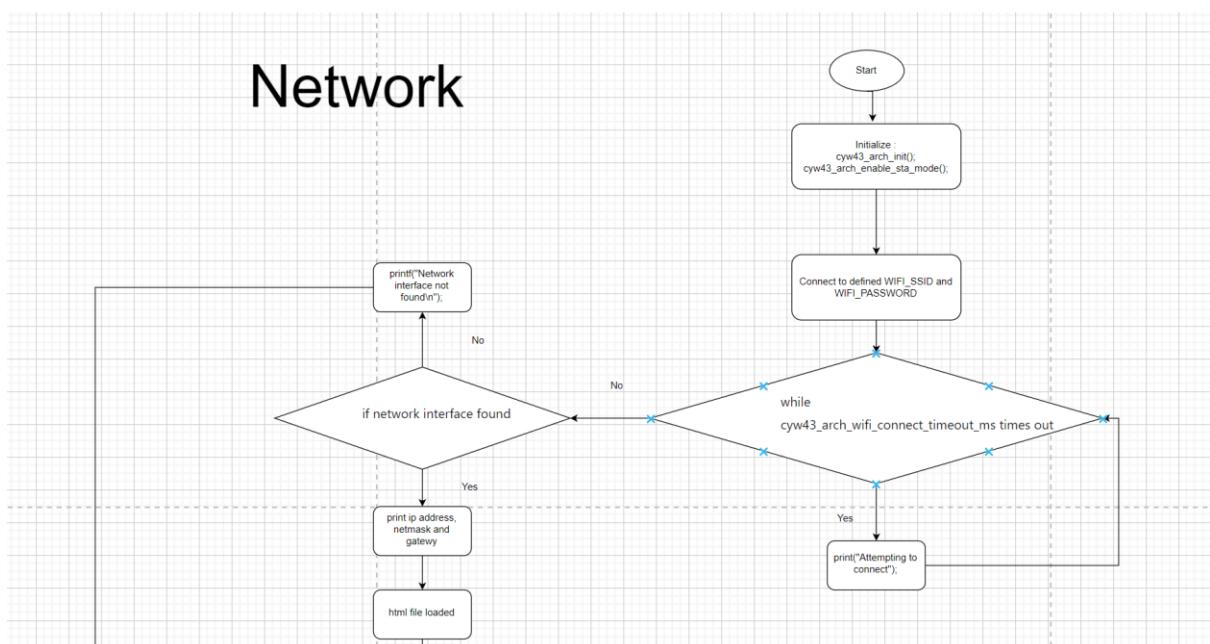


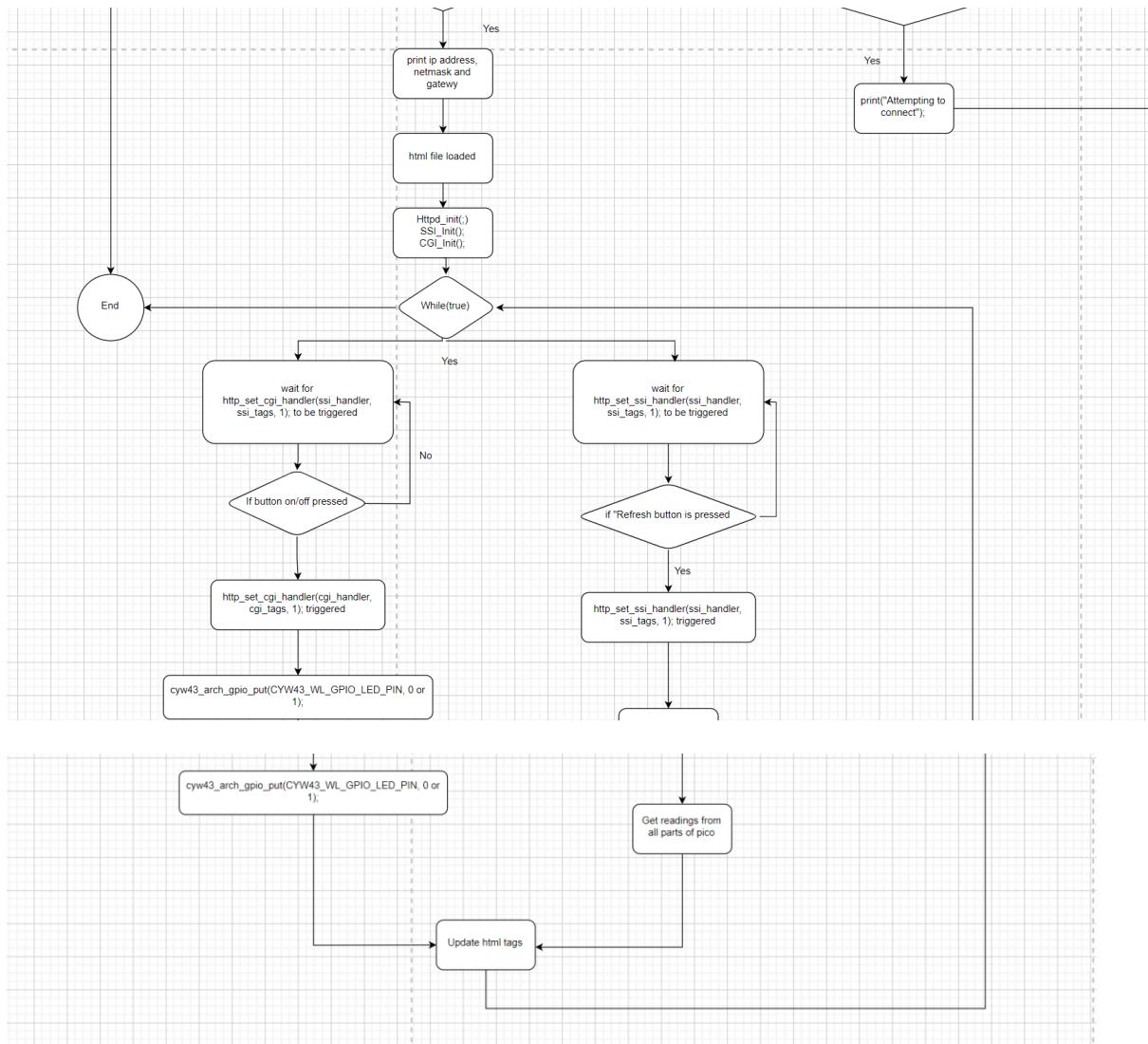
IR sensors

(Line detection) IR sensors

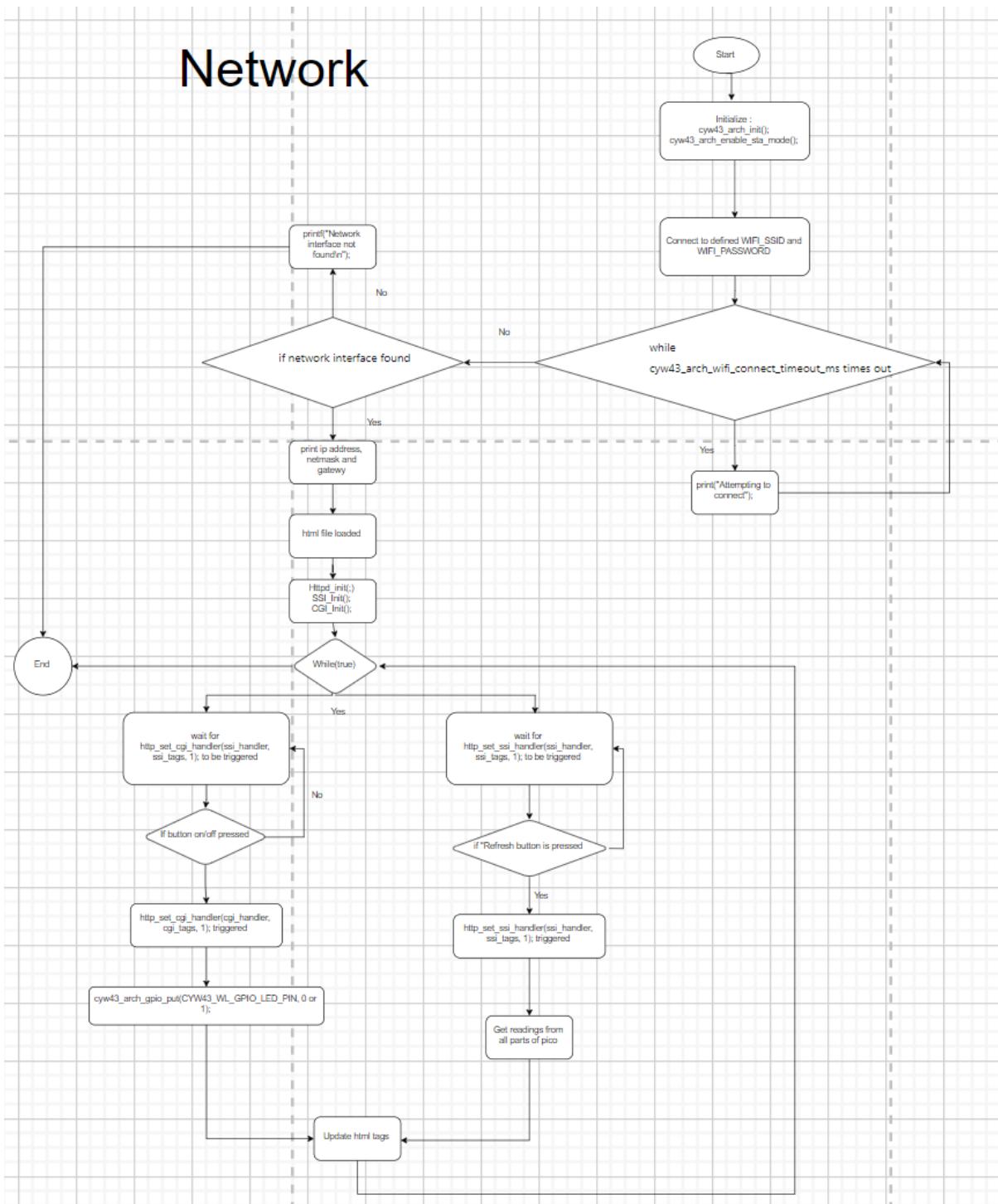


Network

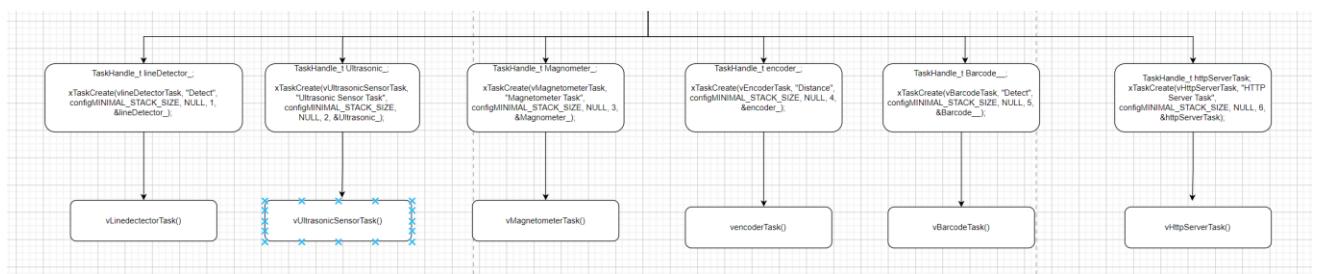
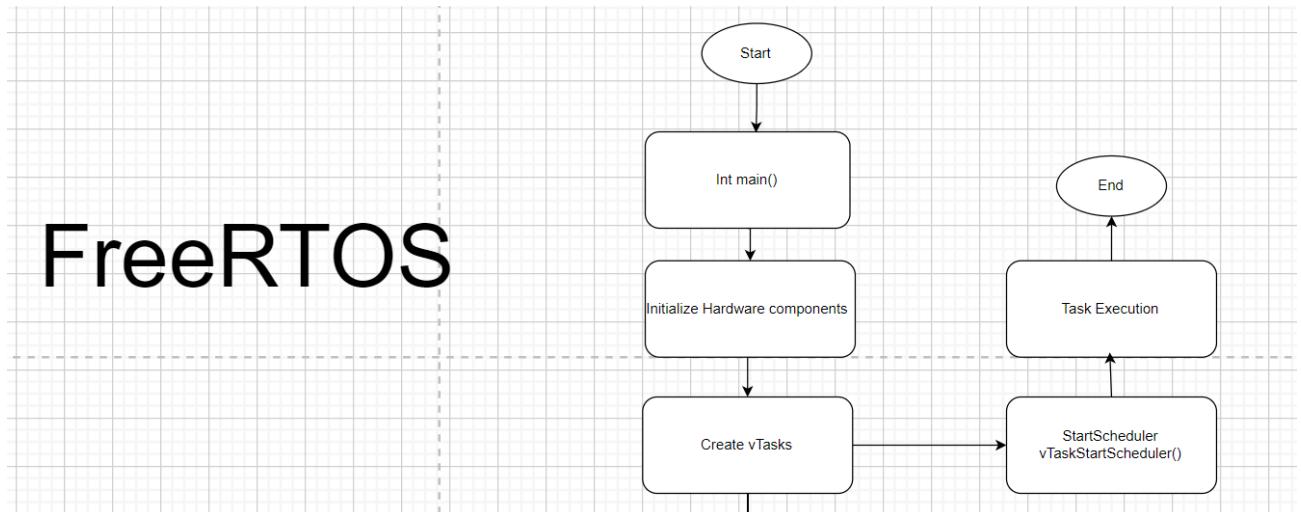




Network



FreeRTOS



FreeRTOS- detailed tasks

