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The final product mimics the behavior of the cruise control feature of a vehicle. The robot senses surrounding objects and responds appropriately. The robot will have two back wheels connected to the PCB which are driven by two DC motors using PWM. To help with sensing objects, the car will have a ultrasonic sensor attached to detect and measure the distance from objects 3cm - 3m away. If the car nears an object, then it will slow down. If the object in front moves forward faster than the robot, then it will speed up.