Microcontroller of Choice:

We decided to use PSoC 6 as the choice of the microprocessor for our project. The first reason is the PSoC can accomplish the real-time requirement, and also one of the features of the PSoC 6 is all pins are editable we can design the function of each pin based on our needs. This allows us to be extremely flexible with our implementation and input/output configuration, controlling more motors as needed or interfacing with more digital sensors instead. The ability to implement Bluetooth would also be extremely helpful for a communication standard with the robot.