PocketBot2 3D visualization - bottom view

- Neodymium magnet: attracts wheel axles, pressing each wheel to the motor shaft.
- Microcontroller: ATXmega128A3, 32MHz
- H-bridge
- Proximity sensors: obstacle detection using modulated IR signal
- Optical encoder: 40 pulses per wheel revolution, 16 ticks per centimeter
- Motor: 60,000 rpm

Ondrej Stanek