Lab 4

1. I noticed that the power and turn ratio are strongly related. I ended up using nTurnRatio of 80 with the nSignedPower of 20. The power should be lower when turning because the robot needs to take the time to turn so there is a recognized change in the reflected color.
2. nTurn needs to be proportional to Power. The power needs to be relatively low in order for the turn to be completed. The calculation of the turn using proportional controller helps in the code because the situations of turning left and right can be written the same because the nTurn can be negative now as well.