1#include <linkbot.h>

CLinkbotI robot;

double radius = 1.75;

robot.driveDistance(8, radius);

2. #include <linkbot.h>

CLinkbotI robot;

double radius = 1.75;

robot.driveDistance(7, radius);

robot.driveDistance(3, radius);

robot.driveDistance(-9, radius);

3. #include <linkbot.h>

CLinkbotI robot;

double radius = 1.75;

double trackwidth = 3.69;

robot.driveDistance(10, radius);

robot.turnRight(90, radius, trackwidth);

robot.driveDistance(7, radius);

robot.turnRight(90, radius, trackwidth);

robot.driveDistance(18, radius);

4. #include <linkbot.h>

CLinkbotI robot;

double radius = 1.75;

double trackwidth = 3.69;

int count;

count = 0;

while(count < 2) {

robot.driveDistance(6, radius);

robot.turnRight(90, radius, trackwidth);

robot.driveDistance(4, radius);

robot.turnRight(90, radius, trackwidth);

count = count + 1;

}

5. #include <linkbot.h>

double width;

double height;

CLinkbotI robot;

double radius = 1.75;

double trackwidth = 3.69;

int count;

printf("Enter the width of the rectangle:\n");

scanf("%lf", &width);

printf("Enter the height of the rectangle:\n");

scanf("%lf", &height);

count = 0;

while(count < 2) {

robot.driveDistance(height, radius);

robot.turnRight(90, radius, trackwidth);

robot.driveDistance(width, radius);

robot.turnRight(90, radius, trackwidth);

count = count + 1;

}

6. #include <linkbot.h>

CLinkbotI robot1;

double radius1 = 1.75;

CLinkbotI robot2;

double radius2 = 1.75;

CLinkbotI robot3;

double radius3 = 1.75;

CLinkbotI robot4;

double radius4 = 1.75;

robot1.driveDistance(7, radius1);

robot2.driveDistance(7, radius2);

robot3.driveDistance(7, radius3);

robot4.driveDistance(7, radius4);

7. #include <linkbot.h>

CLinkbotI robot1;

double radius1 = 1.75;

CLinkbotI robot2;

double radius2 = 1.75;

robot1.setSpeed(2.5, radius1);

robot2.setSpeed(4, radius2);

robot1.driveDistanceNB(10, radius1);

robot2.driveDistance(16, radius2);

robot1.moveWait();

8. #include <linkbot.h>

CLinkbotI robot1;

double radius1 = 1.75;

CLinkbotI robot2;

double radius2 = 1.75;

double trackwidth1 = 3.69;

double trackwidth2 = 3.69;

int count;

robot1.setSpeed(4, radius1);

robot2.setSpeed(4, radius2);

count = 0;

while(count < 10) {

robot1.driveDistanceNB(10, radius1);

robot2.driveDistance(10, radius2);

robot1.moveWait();

robot1.turnLeftNB(90, radius1, trackwidth1);

robot2.turnLeft(90, radius2, trackwidth2);

robot1.moveWait();

count = count + 1;

}