

# ENPM809T HW7

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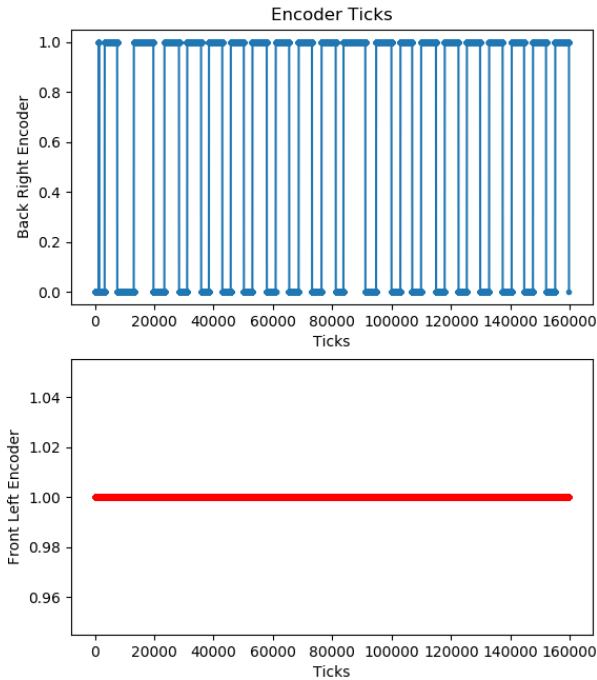
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## 1 Pi Email

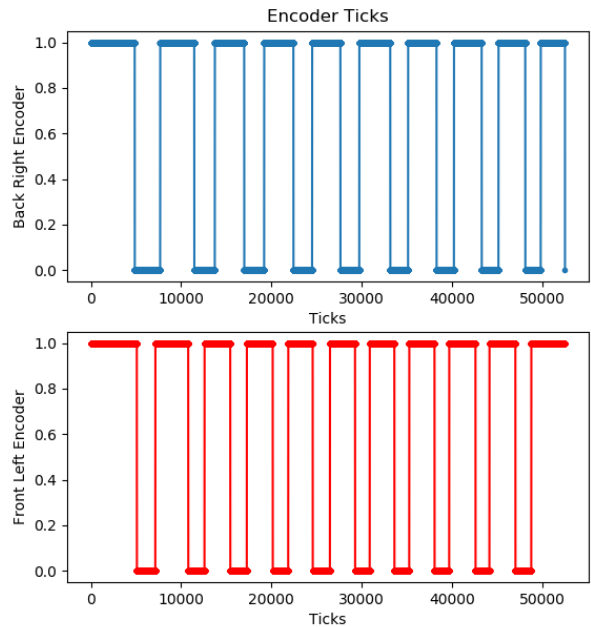
The email was sent from the Pi on 4/22 at 4pm.

## 2 Encoder Plots

Our robot is the Baron.



(a) Right motors only, driven for 1 revolution



(b) All motors driven for 1 revolution

Figure 1: Plots for encoder ticks from 1 revolution

As expected in Figure 1a, the front left wheel (which does not rotate) measures 0 ticks.

## 2.1 Driving in a straight line

<https://youtu.be/VCZY2Yq6tJ0>

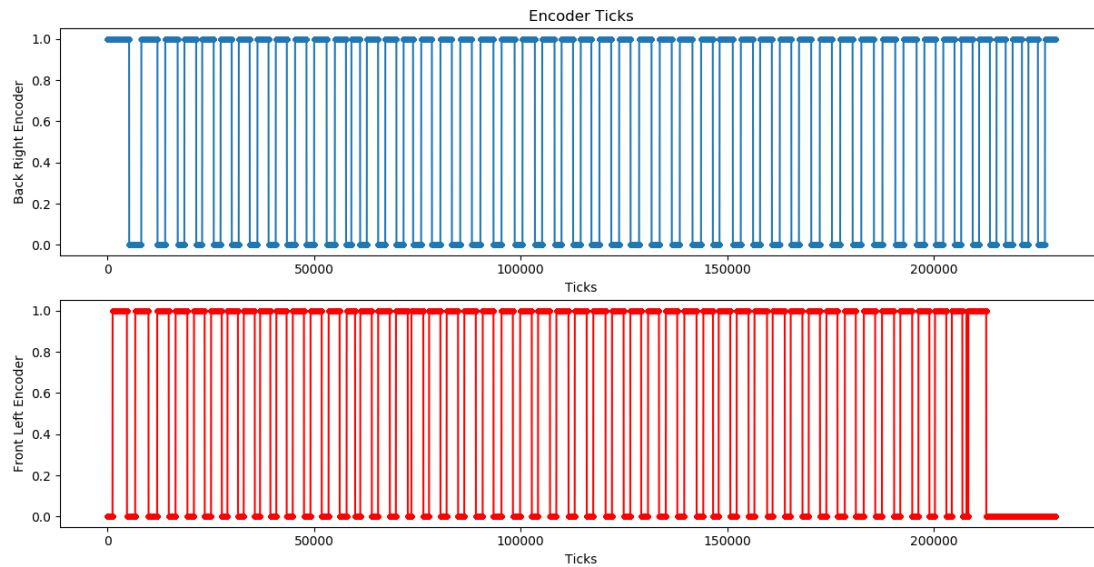


Figure 2: Encoder ticks for driving 1 meter

There is a slight different in the left and right wheel speeds. To compensate for this, the left wheel stops rotating just before the right, which causes the flat line in the bottom graph of Figure 2

## 2.2 Turning

Here can you see a video of the robot driving in a straight line forward and in reverse, and driving through user defined angles. <https://youtu.be/YNzMR494euA>