

Des Marks

11352911

Team members: Russ Vick, John Choi, Ryan Taylor, Elliot Lawrence

## **Lab 4**

### **Links:**

Square - <https://drive.google.com/file/d/0B860ibFHfj3VODJBN2FHRmxFN2s/view>

Square with camera - <https://drive.google.com/file/d/0B860ibFHfj3VdkFMbXAyaXdBUmM/view>

### **Measurements:**

Open-loop starting point to finish point measurement: 5cm

Close-loop starting point to finish point measurement: 10cm

### **Question:**

If getting the robot to trace out a square exactly was really important, then I would use the open-loop control. With open-loop control it is easier to control exactly what the robot does and when it does it. Unlike the closed-loop control, the open-loop control isn't depended upon environmental factors which may change at any given time. I would enhance the code by fine tuning and recalculating the speed of the angular.z velocity and for how long it turns. This is where our team struggled the most with this lab.