

1. The robot keeps moving and working.
2. The robot will keep moving if the loop() takes longer than 100ms, then the odometry will not be correctly updated. Thus the position estimation will be wrong and have some error.
3. The speed is 0.0278m/s.
4. It will set back to (0,0,0) when it crosses the starting line and then keep moving.
5. Without loop closure, because our sensor is not 100% accurate, after the first lap there will be some error because it won't set back to (0,0,0), and after the second lap the error will be bigger and after the third lap the error of the position will become much bigger.
6. When the sparki encounter the start line the position will set to (0,0,0).
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8. 3 hours.
9. Yes.
10. The formula is difficult to understand and the position of the update function.