Is the error you observed in the odometer (without correction) tolerable for larger distances (i.e. circumnavigating the field requires a travel distance five (5) times larger than that used for this lab)? Do you expect the error to grow linearly with respect to travel distance? Explain briefly.

The error observed for the small 2x2 square was overall negligible (millimetres) as we took the time to ensure that the *SquareDriver* method was properly calibrated. However over longer distances these errors may grow. They would not grow linearly with respect to traveled distance however. This is because if the robot is not moving evenly or turning exactly 90 degrees