# **Presentation**

## *Talking points*

* Robot code, libraries, structure, functions and logic
* Robot performance
* Issues that arose, wheel malfunctions and synchronization, faulty IR sensors, wiring issues, code issues.
* Issues with parts of the track
* Pseudo code

Our robot is based upon the provided chassis given to us and works by sensing lines of the track underneath IR sensors at the front of the robot. The robot is programmed to determine what it needs to do to reach the end of the track reliably and consistently. While we have encountered many problems with things such as the code, IR sensors, ECHO sensor, wheel polarity and synchronization, we have endured, and our robot will succeed to the best of its ability. While it may not finish the track perfectly this is the result of converting to an online platform which has made it very difficult to test code consistently. Without the ability to test code in a controlled environment with the supervision of our lab demonstrators, the task was much harder to accomplish.