To: Dr. Berry

From: Team Moravac, Devon Adair and Hunter LaMantia

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Re: Robot Odometry Lab 1

Changing stepTime from 500 to 4000 slows it down a lot

Move1() turns a little bit on startup and on stop

Move2() is exact

moveTo -> move = never goes backwards

runSpeedToPosition->runSpeed = weird slow forward motion before going backwards again

Move3() turns a lot, was very rough

moveTo -> move = crashes

runSpeedToPosition->runSpeed = crashes

runSpeedToPosition->run = stutters in place a few times

2 ft forward = x steps

90 degree spin = x steps

90 degree pivot = x steps

moveCircle() did goodish

PART 5 ENCODERS question

goToAngle() is perfect as far as we can tell from our measurement. It is hard to measure though