Go to Angle (int angle) {

Set a constant speed but different direction

Calculate delay time based upon angle in degrees

If angle is positive

Spin counter clockwise at the calculated speed

Else // angle is negative

spin clockwise in the same speed

Delay for delay time

Stop()

}

Go to Goal (x, y) {

Calculate the angle based on given position

Call the angle function given the calculated angle

Calculate distance to move to next

Call forward to the calculated distance

}

Circle (diameter, direction) {

Set both speeds at a constant speed

Calculate the speed at which to move the diameter

Calculate the difference in the speed based upon the circle diameter

Set the speed of the robot

Call the turn function given the direction left or right

If left make right go faster

If right make left go faster

}

Figure Eight (diameter) {

Set initial Direction to left

Call the circle function with the given diameter the initial direction

Call the circle function again with the given diameter and opposite direction

}

Square (side) {

// side is the length of every side of the square

Call go to goal with the x = side and y = 0

Call go to goal with the x = 0 and y = -side

Call go to goal with the x = 0 and y = -side

Call go to goal with the x = 0 and y = -side

Turn -90 degrees to end up in same direction we started

}