1. During the “delay(100)” the robot continues it last motion, so for the case of a straight line sparki is told to move forward and continues to move forward until the next move command it given and the delay stretches the time sparki is moving forward

2. In each loop sparki would travel further than our code is expecting since assuming it travels a set speed over 100 seconds.

3. 0.0283179158 m/s

4.
    a. X:0
    b. Y:0
    c. Theta: 6.283(radians) or 360(degrees)

5.
    a. First Lap:
        i. X:-0.02
        ii. Y:0.05
        iii. Theta: 355.93 degrees
    b. Second Lap:
        i. X:-0.03
        ii. Y: 0.06
        iii. Theta: 711.85 degrees
    c. Third Lap:
        i. X: -0.03
        ii. Y: 0.07
        iii. Theta: 1075.35 degrees

6. When the left, right, and center reading are below the threshold we set x, y, and theta to zero since we can assume that we are at the start location

7. Jordan Smart, Lucas Laughlin, Casey Tran

8. We spent the time in lab plus around 2 hours on getting our code working and around 30 minutes on the writeup.

9. Yes our code does work as expected.