import serial

import time

import math

import os

xpos\_robot = int(raw\_input("Robot X Position: "))

ypos\_robot = int(raw\_input("Robot Y Position: "))

xpos\_goal = int(raw\_input("Goal X Position: "))

ypos\_goal = int(raw\_input("Goal Y Position: "))

distance = math.sqrt((xpos\_goal - xpos\_robot)\*\*2 + (ypos\_goal - ypos\_robot)\*\*2)

angle = round(math.degrees(math.atan2((ypos\_goal - ypos\_robot), (xpos\_goal - xpos\_robot))))

print distance, angle

os.system('/root/rc\_wheeled\_auto/rc\_wheeled\_auto ' + str(angle) + ' ' + str(distance))