* Navigation Algorithm
  + <http://wiki.ros.org/navigation> (ros nav library if we choose to go down this route)
  + <https://github.com/ros-planning/navigation> (a thought)
  + <https://www.youtube.com/watch?v=WLVfZXxpHYI> (arduino)
  + <https://www.mathworks.com/help/simulink/supportpkg/arduino_ref/encodersensors.html> (encoder)
  + <https://www.allaboutcircuits.com/projects/control-a-motor-with-an-arduino/> (?)
  + <https://www.youtube.com/watch?v=XrJ_zLWFGFw> (arduino with motor)
  + Navigate through a room without hitting anything
  + Needs to travel through a room in a way that the entire room is scanned.
    - Can't just go around the outside of a large room, it needs to do the center of the room as well.
  + Relatively efficient
    - Don't want to go over areas we’ve already been in without doing the whole room first.
    - thought: have the robot move to a specific spot on the floor each time to scan the ultrasonic? or just update constantly I guess and compare from half a second ago or something like that
    - <https://www.youtube.com/watch?v=n-gJ00GTsNg> (ultrasonic)
    - I already have PIR code and sensor (from sensors)
  + Depending on how the sensors work, especially the passive IR sensor, we may need to stop periodically to take a capture of a room, then another some time later to see if there was movement/change in IR.
    - <https://web.phys.ksu.edu/vqm/tutorials/re/remotepg4.html>