The original method for moving the robot was to manually rotate the motors. An easier method is to use the built-in drivetrain. The parameters it accepts are the motors for the drivetrain and distances. There are built-in methods for moving, rotating, setting speed, and brake type. This was an easier and quicker way to operate the drivetrain.

**[Insert photo of drivetrain configuration]**

However, when testing, the drivetrain was inaccurate with its distance and rotations. The inaccuracies are below:

* Distance: +2 in.
* Rotation: +10 deg.

The drivetrain also accepts certain sensors, including the inertia and GPS sensor. This should allow for more precise movements. Therefore, we ordered an inertia sensor to solve the inaccuracies.

**[Insert photo of drivetrain sensors configuration]**

Using a drivetrain, we can program specific steps for the autonomous period. However, the programming skills challenge would be more difficult and would create more inaccuracies. Therefore, a GPS sensor would allow the robot to move to specific positions. So we ordered a GPS sensor.





