

goToAngle(goal θ)

turn θ = goal θ - current θ

while (|turn θ | > 0.5°)

{

if (turn θ < 0.5°)

rotate Right

else if (turn θ > 0.5°)

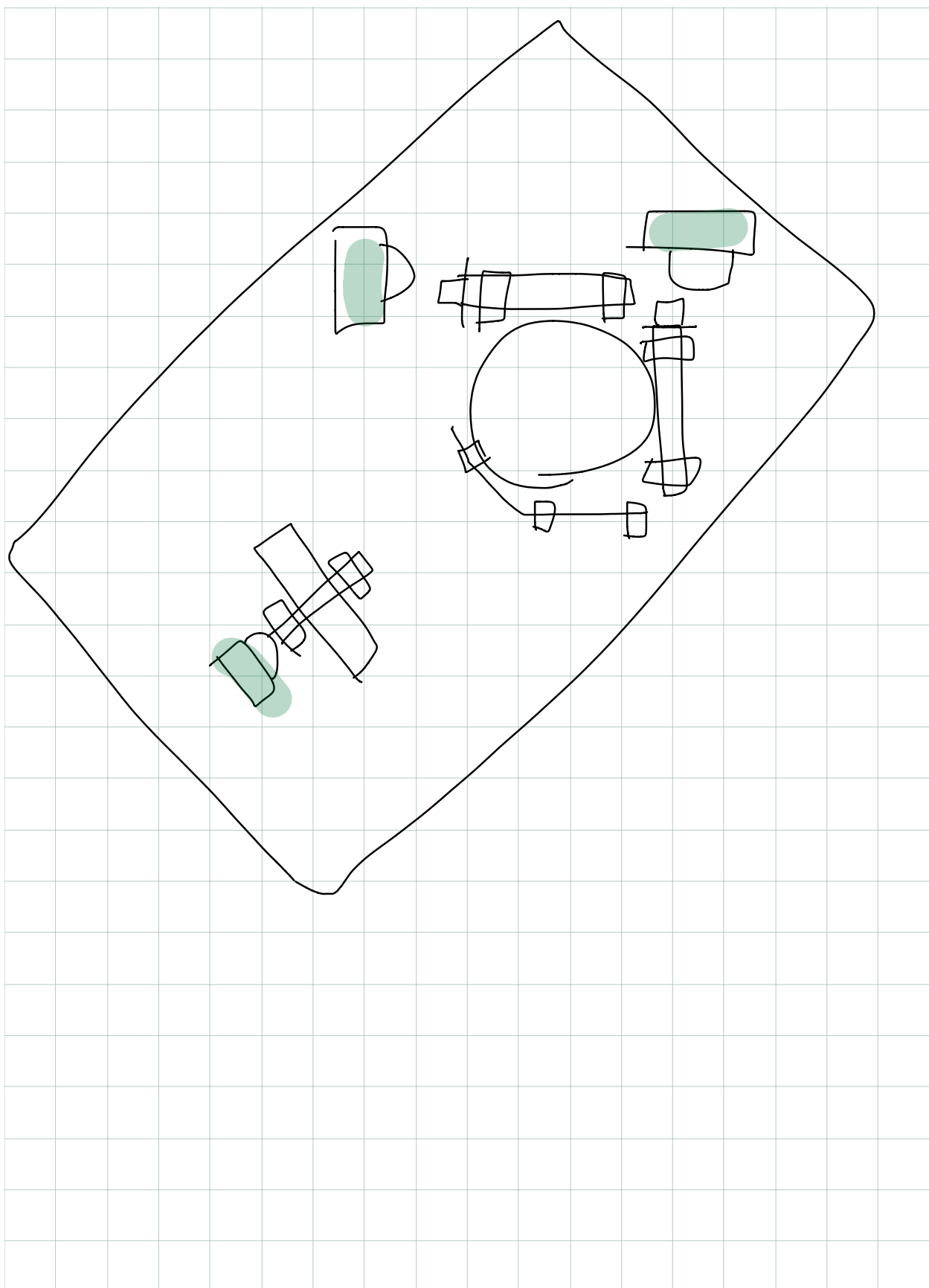
rotate Left

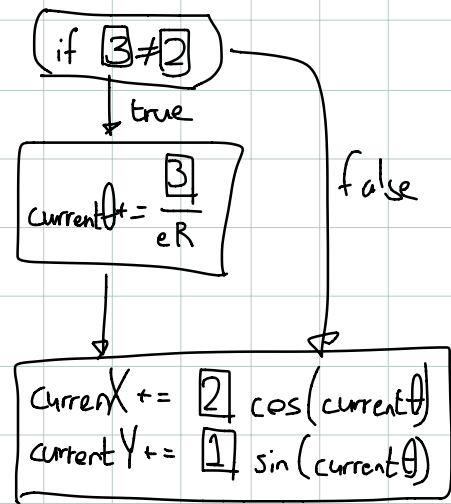
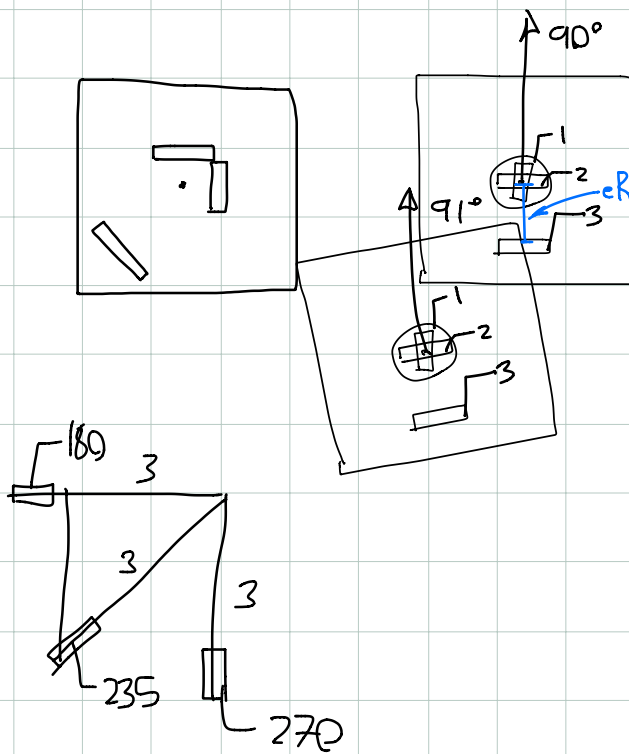
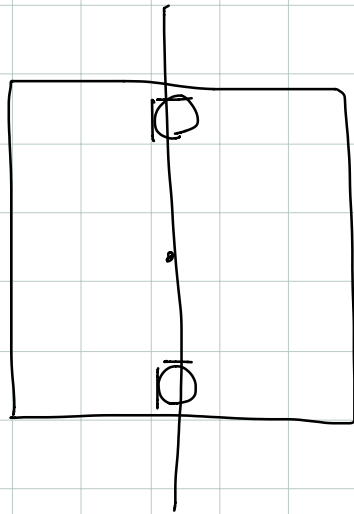
turn θ = goal θ - current θ

}

stopMotors()

wait 100 milliseconds



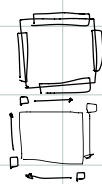


Obstacle detection methods:

- Bumpers on all sides

- Ultrasonic on all sides

- Accelerometer obstacle detection



inefficient resource usage

← ramp.

- Expected vs. Actual (motor slippage + expected θ, r, x, y)

can have parameter
robot & field
dimensions

- EOPD on a turret

- Array of field - each unit is marked blocked, unblocked, or unknown

Pathing algorithm

