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PS1

Starting with the STDR Open Loop Commander file, I went ahead and refactored the code to my own liking. This process included placing the velocity commands in separate methods (*move_forward*, *make_turn*, *make_right_angle_turn*, be*_stationary*) as to dramatically cut down with repeated code. These methods, respectively, allow the robot to move forward for some time duration, make a turn in some direction (positive or negative) for some duration, make a right-angle turn in some direction (positive or negative), and actively be stationary for some time duration.

With these separate methods, the given task was then completed by calling these methods in some sequential order, with varying parameters, so as to direct the robot manually to the upper-left corner of the maze. This approach, however, is not perfect; since the simulator includes simulated physics and overadjustments/underadjustments, the node - by random chance - will occasionally collide into the maze and not be able to complete its run.

The video provided is a successful run of the node, and demonstrates its navigation to the upper-left corner of the screen.