Method changed
- In_Range()
    o sensor_proximity.cc – line 41

Method added
- DistanceToCrossing()
    o sensor_proximity.h – line 96
    o sensor_proximity.cc – line 37

Location where temporary variable was defined but is now replaced by call to new method
- sensor_proximity.cc – lines 45-48 and 52-55

The new method DistanceToCrossing() is replacing the previous temporary variable of the same name. The method calculates the angle difference between 360° and the angle of the lower sensor of either or both of the sensing and sensed entity. Instead of reusing some temporary variable multiple times throughout the code, it's replaced by a method that accomplishes the same task. So, what this method does is that it computes the angle distance between the robot's lower sensor and crossing line at a 360° angle to aid in determining whether the sensed entity is within range of the proximity sensor of the sensing robot.