

Project 1

Module 3: Exercise 1

Drive 10 cm, rotate, etc.

Module 5: Problem 2

New Feature - Implemented resolving the corner case of the robot coming to a full stop by adding a wait time, driving backwards, and turning around to continue the process.

Best Cases:

1. going from point A to point B where there are a lot of moving objects/people walking
2. situations where the objects are small and moveable

Corner Cases:

1. comes to a wall/heavy object - cannot remove object, will stay stopped forever

resolution: implement turning around

2. distance sensor only covers a certain area - cannot detect things below or above or on the sides

resolution: implement having the servo rotate left, right, up, and down (probably use a pivot of some sort for up and down directions)