1. The robot continues its last movement command for the specified time. For example:

sparki.moveForward();  
delay(100);

will move the robot forward for .1 seconds then continue code execution.

1. If the loop call takes longer than 100 ms, then the calculated distance will drift over time. We are using a precalculated speed to determine Sparki’s position over time. If the time is not perfectly accurate then the calculated location will not be accurate.
2. We calculated an average speed of 0.027845 m/s during the 30cm test.
3. Ideally, the calculated pose should be (0,0,0). This would indicate that Sparki has perfectly calculated its displacement from the datum.

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