**How does your program work?**

We wrote a command function which depending on the input does different commands. For example, using the argument ‘r’ will reset the robot. The argument ‘dr’ will ask for the velocity and radius and then run the drive function. The drive function takes the arguments converts them into hexadecimal then splits the hexadecimal into the highs and lows. Then it passes the highs and lows into serial\_connection.write(chr(137)). The penta function uses the drive and time function to have the robot move in a pentagram shape.

**What design decisions did you make? Describe your method carefully.**

We decided to convert the numbers in the drive function instead of the command function. This is useful because when we call the drive function elsewhere, such as the penta function, we do not have to remember to convert it.

**Does your program actually work? How well? If it doesn’t work, can you tell why not?**

Most of the functions works. Our main problem is with the drive function. We were unable to successfully convert from decimal to hexadecimal and the highs and lows.

**What partial successes did you have that deserve partial credit?**

The functions such as reset, clean, safe and passive work correctly. We believe penta would work if we could get the conversions for the drive function to work.

**List the names of each person that worked on the project along with their contributions to the final result.**

Jeff did the majority of the coding and organizing.

Franco helped with a lot of the coding.

Kaitlyn offered suggestions and wrote the report.

Noah also offered some suggestions.