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1. During the Delay(100) statement, Sparki continues executing its previous statement. We placed the odometry code after the delay statement to measure where the robot was placed at the end of the execution loop.
2. We measured the time to execute each loop and calculated the position based on that time rather than forcing each loop to take 100ms.
3. Wheel radius: 2.55 cm; axel length: 8.45 cm; motor speed: 2.7724 cm/s
4. See code
5. When the robot arrives at the start line a second time it should show x= 0, y=0, theta=0. In actuality all three numbers are slightly negative. X and Y have errors of 1-2cm , theta is about 5 degrees off.
6. We could reset it to x=0, y=0, theta = 0 every time it hits the start line.