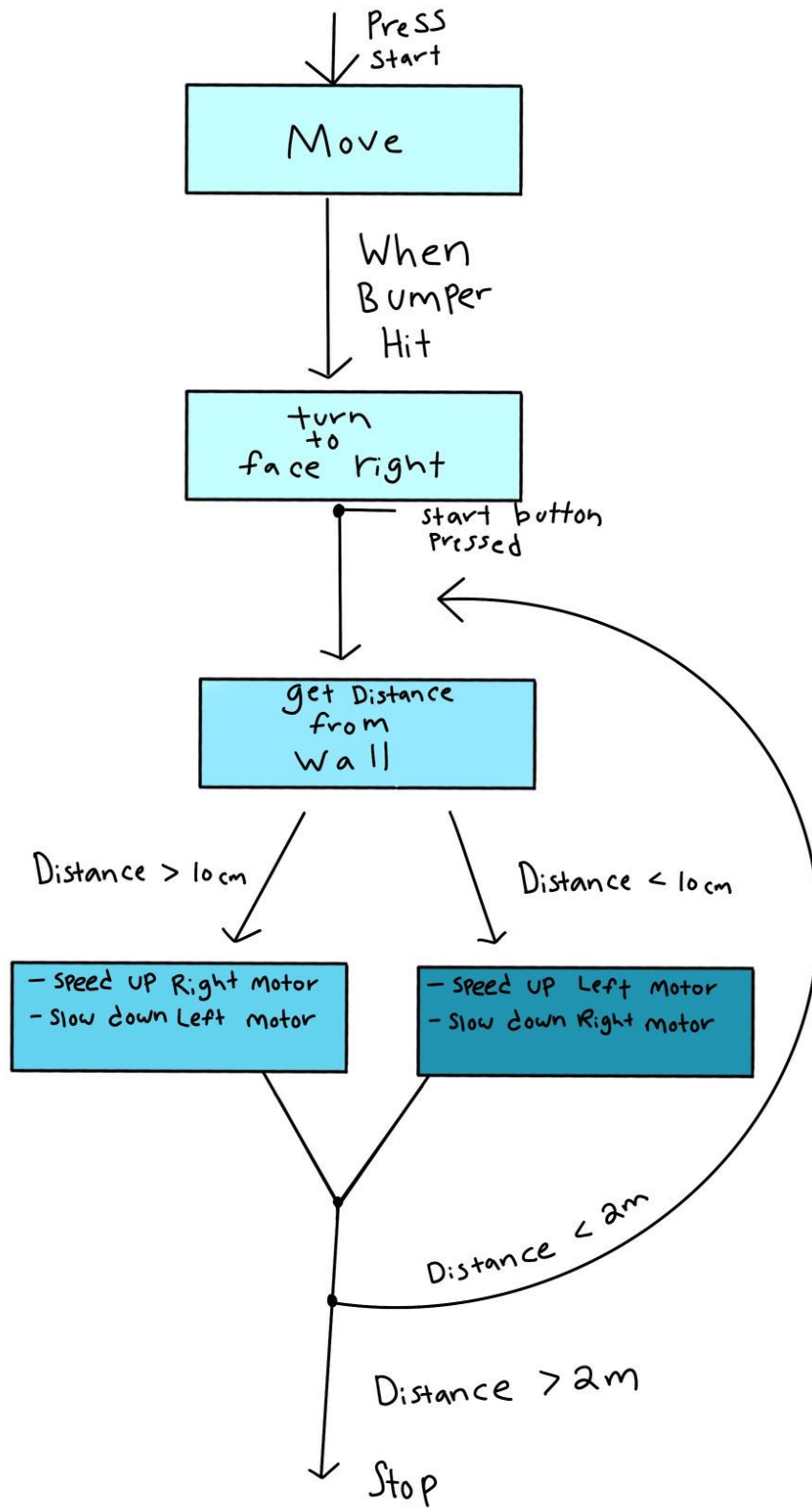


Lab 2 Reflection: Team Every-Detail LLC

1. Read 'The Task' in the Lab 2 description, then explain which motors and sensors you are using for each part of the task and what type of robot you are building.

In this lab, we will be using a differential drive robot. For the first part of the lab, in which the robot will be moving towards the wall until it is less than 30cm from the wall, we will be using two motors to move the two wheels and the bump sensor to tell us when the robot has reached the wall. In the second part of the lab, we will again use the motors to control the robot, the ultrasonic sensor to tell us how far away from the wall we are at any given time, and the bump sensor as a safety precaution if the ultrasonic sensor fails.

2. Draw a flowchart representing your approach.



3. Turn your flowchart into pseudocode. Think about the hardware you will use, the different states the robot may be in at any given time and any edge cases that may arise.
 - While (bump sensor not pressed)
 - Move motors forward
 - Stop Motors
 - Move robot to face right
 - While (distance_traveled < 2m)
 - If distance_from_wall > 10cm
 - Move right motor faster
 - Move left motor slower
 - Else
 - Move left motor faster
 - Move right motor slower
 - Distance_traveled = (time elapsed in current iteration) * (velocity of robot)
 - Stop Motors
 - Robot Beep