**Project 1 Design Review Comments/Suggestions**

1. Using one-eighth of a rotation to calculate distance would be more precise than using the full circumference of the wheel.
2. There is no floating point capacity in the EvalBot, so we will need to measure in increments.
3. An end state should be added to our display flow chart.
4. Error could be measured for distance and left/right movement (slippage).
5. The distance travelled on a turn is different for each wheel—should be considered when measuring distance travelled.
6. Power doesn’t change speed linearly.

* Start by setting motor at 10-15% and stepping up by 5% increments
* Measure time between pulls to calibrate

1. Mapping table: what you want wheel to do vs. actual
2. Display speed?
3. FreeRTOS structure, port autonomous code over
4. Presentation idea: PID\_Controller, how it works