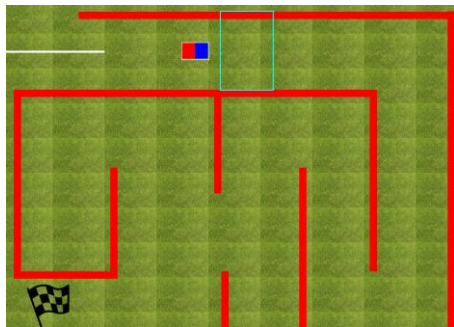


What is being tested	Expected Output	Actual Output
Transition from white line to red wall scanning	Keeps going in a straight line	Keeps going inn a straight line
First Corner	Turns downwards once it is closer to the wall	Turns downwards once it is closer to the wall
Second and Third corner	Turns to the left then up	Turns to the left then up
Fourth and Fifth corner	Turns to the left then down	Turns to the left then down
Turn through the gap	Turns 90 degrees to the right	Turns 90 degrees to the right but occasionally does only a 45 degree turn
Turn right then up	Turns 90 degrees and then up	Turns 90 degrees and then up
Turn around at top	Turns around at the top to face back down again	Turns around at the top to face back down again but occasionally crashes into the top wall
Last Corner and final straight	Turns to the left and straight to finish line	Turns to the left and straight to finish line but occasionally crashes into the wall

What is being tested	Expected Output	Actual Output
Transition from white line to red wall scanning	Keeps going in a straight line	Keeps going inn a straight line

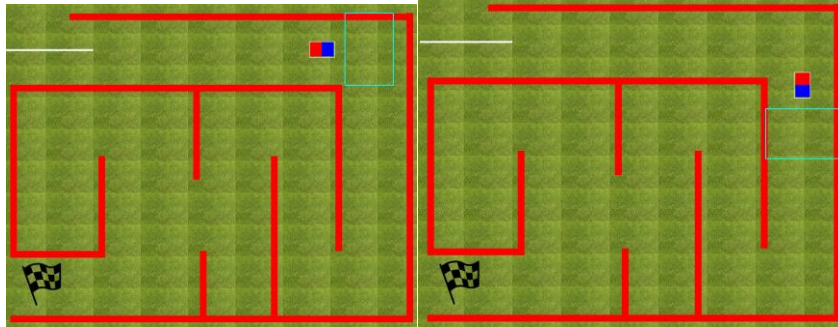
At the beginning the robot transitions from scanning the white line to the red walls for its guidance system.



This matches the expected output.

What is being tested	Expected Output	Actual Output
First Corner	Turns downwards once it is closer to the wall	Turns downwards once it is closer to the wall

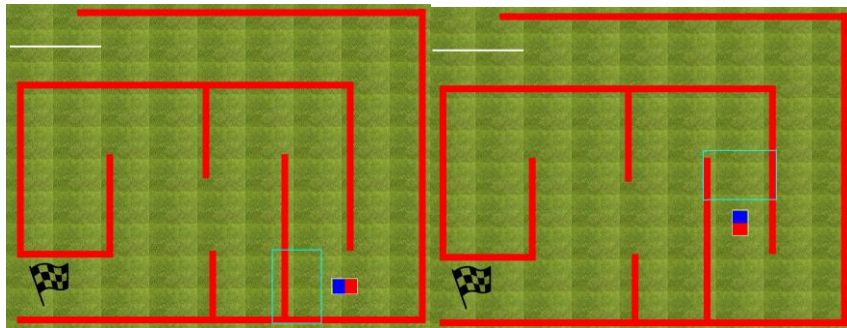
After the robot has travelled across the entire top of the maze it turns downwards at a 90 degree angle.



This is the expected output

What is being tested	Expected Output	Actual Output
Second and Third corner	Turns to the left then up	Turns to the left then u

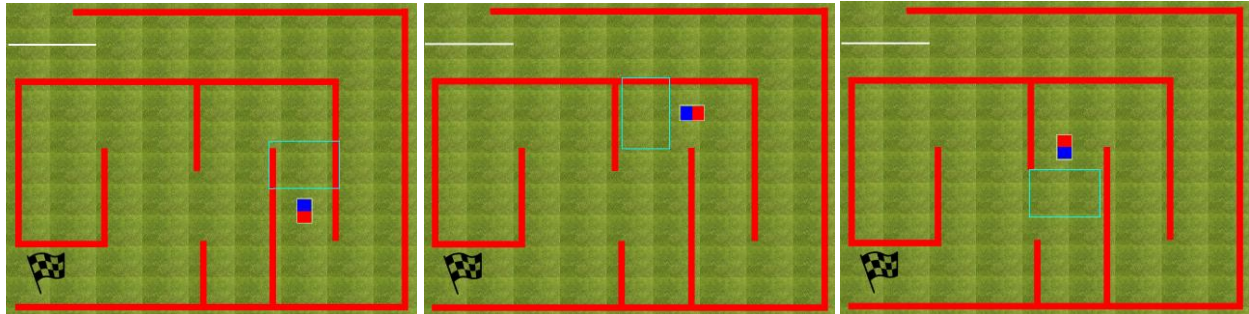
Once the robot has travelled down to the bottom of the maze it does a turn to the left then travels for a short time then travels upwards.



This is the expected outcome.

What is being tested	Expected Output	Actual Output
Fourth and Fifth corner	Turns to the left then down	Turns to the left then down

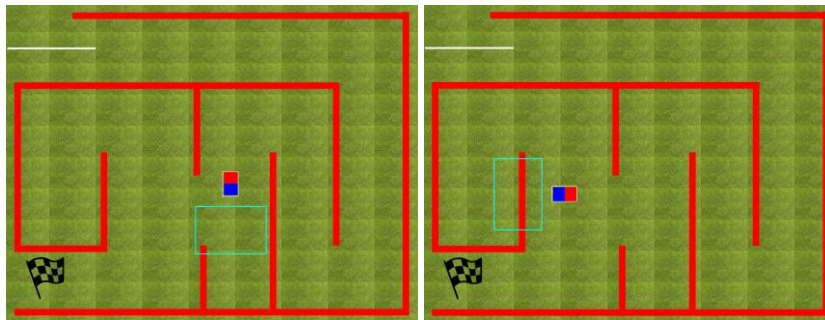
After the robot has completed a U-turn at the bottom of the maze it goes upwards and does another pair of turns resulting in it moving downwards.



This matches the expected results.

What is being tested	Expected Output	Actual Output
Turn through the gap	Turns 90 degrees to the right	Turns 90 degrees to the right but occasionally does only a 45 degree turn

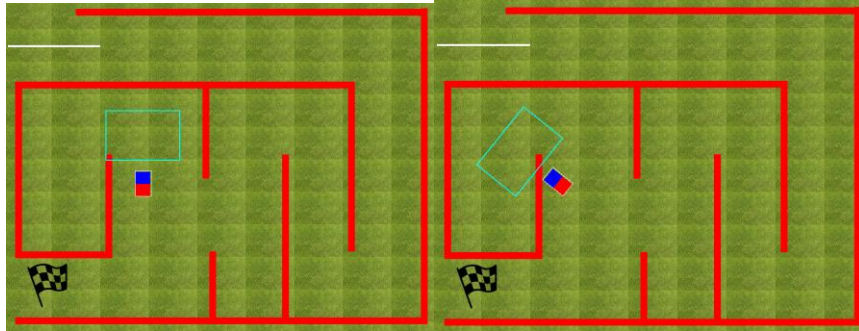
After the fifth corner the robot turns right through the gap in the red 'wall' and goes straight across



This is the expected output from the code.

What is being tested	Expected Output	Actual Output
Turn right then up	Turns 90 degrees and then up	Turns 90 degrees and then up

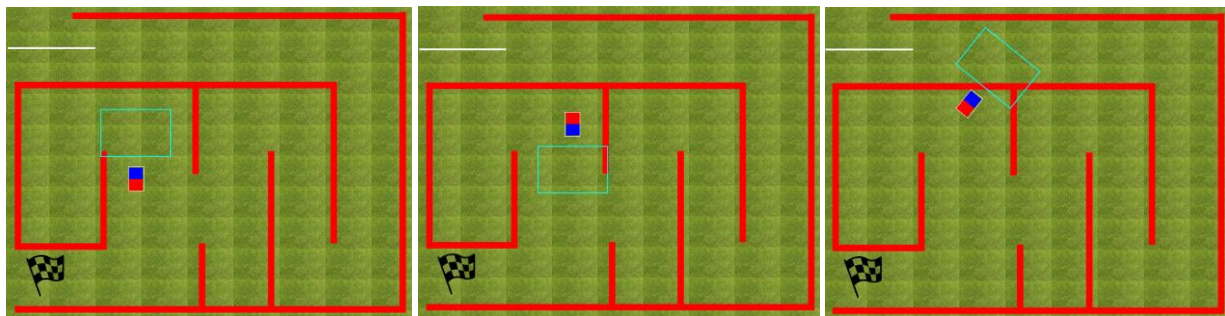
The robot makes a 90 degree turn upwards after passing through the gap. However, in the process of testing it was discovered that the robot didn't always make a 90 degree turn, occasionally it would make a 45 degree turn. This was not expected as there was no call for a 45 degree turn anywhere in the code. It is believed to be an error with the server3.cpp as the code that was executed was the exact same each execution.



The output partially matched the expected output but occasionally failed due to the unknown error

What is being tested	Expected Output	Actual Output
Turn around at top	Turns around at the top to face back down again	Turns around at the top to face back down again but occasionally crashes into the top wall

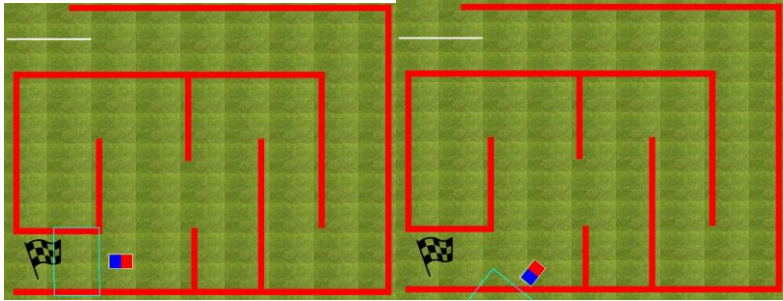
The robot is moving vertically and once it reaches the top wall it completes a 90 degree turn twice which results in it facing downwards. However, in the process of testing it was discovered that the robot didn't always make a 90 degree turn, occasionally it would make a 45 degree turn. This was not expected as there was no call for a 45 degree turn anywhere in the code. It is believed to be an error with the server3.cpp as the code that was executed was the exact same each execution.



The output partially matched the expected output but occasionally failed due to the unknown error

What is being tested	Expected Output	Actual Output
Last Corner and final straight	Turns to the left and straight to finish line	Turns to the left and straight to finish line but occasionally crashes into the wall

The robot will make a 90 degree turn to the left and continue straight to the finish. However, in the process of testing it was discovered that the robot didn't always make a 90 degree turn, occasionally it would make a 45 degree turn. This was not expected as there was no call for a 45 degree turn anywhere in the code. It is believed to be an error with the server3.cpp as the code that was executed was the exact same each execution.



The output partially matched the expected output but occasionally failed due to the unknown error