

# ME131 Lab 9 Deliverables

---

Trey Fortmuller - 26037758

1. Our lateral controller is a simple P controller which uses the max and min location values to determine the camera's relative distance to the centerline of the lane. This relative distance to the centerline is the input to our proportional controller, a  $K_p = 10$  was chosen for a longitudinal velocity  $V_x = 20$ .
2. <https://drive.google.com/open?id=1muAiOa6J-voNvk7c5j7SIUMHtKSE5-iD>