Subhi Alsous:

* Used the online buggy simulator to simulate how the line tracking is affected by varying the distance of the sensors from the motor/battery and other factors
* Decided on the sensor type, geometry and alignment that the control would be based on
* Looked up various sources to as how to use the values given by our sensors in the implementation of the PID controller
* Took a closer look at how will the PWM be applied to both wheels and it’s contribution to the control algorithm