**PID project**

**P** Proportional

The proportional means that the car will steer in proportion to the cross-track error.

**Steer = -Kp \* cte**

**I** Integral

The integral sums up all cross-track error, to the current time

**Steer = -Ki \* sum(cte)**

**D** Derivative

the change in cte w.r.t time

**Steer = -Kd \* dt(cte)**

I manually tuned PID parameters

pid.Init(0.04, 0.004, 0.5);

P = 0.04

I = 0.004

D = 0.5

These params work fine on my machine check the attached video