**Software Week 5 Modifications :**

Main architecture :

* Switch from threads to classes with methods, instead of creating a new thread for every task, just call some methods from the classes to do the tasks
* This reduce the number of threads required -> increase robot computing speed and reduce the risk of program failure due to overhead

Localization class:

* Modification of the localization speed, so it can localize itself AND correct its position/orientation under 30 sec <- was done by increasing the speed of rotation of the robot and correcting the robot using line detection once instead of two

Light sensors:

* Modification of the line detection algorithm: instead of using an absolute value as reference for line detection, we switched to a light differentiator (calculate the difference between normal sample and black line sample)

TravelToTree class:

* Modification of the travelling and correction algorithm
* Travelling: instead of travelling in diagonal, we will now travel only in x and y direction to facilitate the position correction and accuracy of the robot
* Correction: instead of correcti g the robot position and orientation at grid intersection, we will now correct its orientation and position every time it crosses a line to increase the accuracy of the travelling and reduce the time consumption of the correction