**Final Interim Report**

Completed So Far

* Motors have been installed on Robot Chassis and connected through L293 motor driver chips to Raspberry Pi using GPIO to control direction.
* We are able to command forward, left and right turn functions on motors having all work in unison.
* IR Line Sensor is set up and wired, with code created to generate Boolean readings from each of the 8 reflectance sensors. Data is returned at a regular interval set by the programmer.
* Python code created to solve maze using left-hand rule algorithm.
* Code written to remember best path taken by robot and return it to the start of the maze.

Still Needs to be done

* We need a more powerful and reliable power supply in order to consistently power RPi and all motor components, speed of the motors as well as generating the correct timing to execute turns.
* Line sensor, power supply (TBD), RPi and breadboards need to be secured and wired to Robot chassis.
* Code for line sensor, motor functions and maze algorithm need to be combined and tested on completed robot.