Project Title: PID Controller

The aim of the project was to use a PID controller to control the steering angle and speed of Udacity car utilising some of the lessons covered in the class. The projects translate the python implementation in the class to C++ to run the Udacity car. The simulator provided the cross track error (CTE) and velocity (mph) and the PID controller utilise this information to compute an appropriate steering angle and speed. The PID controller is implement in the PID.cpp file. The steering angle and speed are computed in the main.cpp between lines 70 – 82.