**How does your program work?**

The interface was modified to check is the infrared distance sensor, known as the Light Bumper. Next two functions where created in the read file. One has the robot follow the wall. The other is used by the wall as a PD Controller to correct any errors.

**What design decisions did you make? Describe your method carefully.**

We took the square root of the signal strength form the light bumpers. It made the numbers a lot easier to work with. We also decided to use the right light bumper because the sensors on the robot are not perfectly symmetrical. The right bumper was on the middle of the side of the robot while the left one was farther up.

**Does your program actually work? How well? If it doesn’t work, can you tell why not?**

Yes, the robot follows the wall with minor oscillating. When the robot reaches the end of the wall it turns and drives down the opposite side. If we move the wood wall away from the robot it will move back closer to the wall.

**What partial successes did you have that deserve partial credit?**

The robot does everything it is supposed to do.

**List the names of each person that worked on the project along with their contributions to the final result.**

Franco Godoy corrected mistakes on task 1, worked on task 2.

Jeffrey Knoll also corrected mistakes on task 1, worked on task 2.

Kaitlyn Ash worked on task 1, helped with task 2 and wrote the report.

Noah Wartzack