## Recommended Assessment

## **Line Following**

- 1. Why do we need to use color thresholding and a binary image for finding the objects of interest?
- 2. Using the same image provided in the lab, explain the procedure to get the robot angle using the center of the blob of interest.
- 3. Why do we use a PD controller for the turn speed command of the robot instead of directly feeding the angle error?
- 4. Why do we feed back the integral of the turn speed when calculating our error from the center?