This week we have:

Started simulating a state space model in Simulink. We are currently trying to find a good PID controller that might be able to balance the robot.

Created a skeleton program for the robot that will run concurrent tasks for the balancing, running and following of a line.

Continued the work with the line following algorithm. We now have an algorithm ready for implementation and testing.

Tried to communicate with the robot using Matlab via a bluetooth link. But for now we are only able to transfer information from Matlab using the USB port.

Also quite a lot of time was spent preparing the presentation of today.

Next week we will:

Continue simulation of the model and add characteristics for the light sensor which gives integer values and is pretty inaccurate.