Abstract

In this paper, the analysis for data collected for two different line follower robots vehicles are presented. Keeping the hardware identical, the two vehicles were programmed with two different algorithms. When taking a turn, a correlation between its turning angle and the angle of line turn was observed. To find that correlation, experimental data was collected after varying critical parameters. After that, a mathematical representation was derived to calculate the required turning angle for any line angle.

References


**Index Terms**

Computer Science

Circuits And Systems

**Keywords**

Robotics  Algorithm  Turning Angle  Line Follower.