Avoiding Obstacles while Following a Line

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We achieved...

- Line Following
- Obstacle detection with a marker
- Avoiding an obstacle while following a line
Line Following

- Detect the line
- Project into 3D
- Calculate the **error in pitch direction**
- Calculate the **error in yaw direction**
Obstacle Avoidance

- Detect marker
- Calculate the distance to marker
- When obstacle too close
  --> increase the height
- After passing: go back to standard height
How it worked together