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| Task. No.: | 3 | Points: | 5 | Lane following and obstacle detection |

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| Objectives:  1. Using Simulink. 2. Working RGB camera. 3. Using image processing algorithms |

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| Description: The goal of this exercise is to run application of autonomous lane following and obstacle detection using the QCar. |

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| Step | Action |
| 1 | Use Simulink implementation of lane following with obstacle detection.  Simulink implementation |
| 2 | Change the parameters of the UserInputs subsystem to detect the lane. You can define the max/min values used for the HSV thresholding, the lane which we want to follow, the stopping distance to an obstacle and the maximum speed of the QCar.  Example of values that can be defined for the QCar |
| 3 | The output should be like the following image.  Image from the view of the QCar |

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