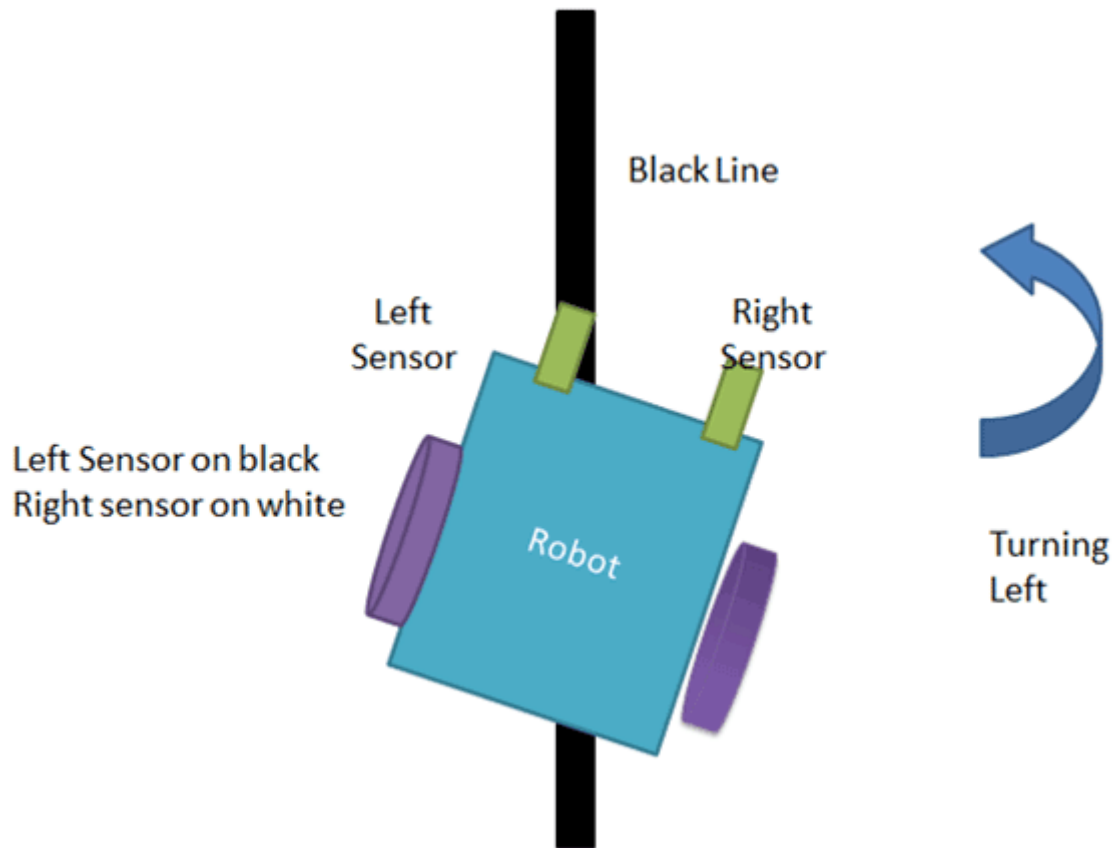


If left sensor comes on black line then robot turn left side.



If right sensor sense black line then robot turn right side until both sensor comes at white surface. When white surface comes robot starts moving on forward again.