You can make the robot make partial turns by # degrees depending on the distance

Say: your going forward and using the ultra sonic sensor as a guide (one way to continue through the maze)

-if the robot is too close to the wall you can partially adjust how much to turn (rather than a 90 degree turn) to keep it in track. (you also stop make teh small adjust and continue forward.

If it's too far from the wall it can adjust it's distance to stay within the distance between the wall

Concept of the turing would be based on time/ speed. (Mostly time, but speed affects the time to take to turn.)

0-255

-trial and error (Is the best way to go with this!!!)