Strategic: Finding the line

Problem: when the robot make the turn after hitting the object (touch sensor) or detected a intersection (IR sensor), the robot is off the line just a bit

Idea:

Because generally the line will be on the right of the robot’s color sensor

And =========== the line will be on the left of the robot’s IR sensor

So, we want to turn left at a small angle once it used the IR Sensor, and move forward. Once the color sensor detect the line, it turns back the same angle that it turned.

And the other way around for touch sensor