Based on the calibration equations, and , we know how the gain (g) and trim (r) will affect the robot movement. Since we move in straight line, , and therefore and just reduce to . Hence, we only care about the left part of the equation. When the trim is positive as remains constant, , and hence . It makes the right wheel move faster than the left wheel, and the robot will tend to go left. In the opposite, when the trim is negative, the left wheel moves faster and thus the robot steers right. Furthermore, in both equations, and is proportional to . It means that as we increase or decrease the gain, and and will also increase or decrease respectively. However, to compensate this change in , we will also have to scale trim proportionally. Smaller gain requires fewer trim as the equations suggest.