This is the simple experiment Romi is moving at power of 40 on both wheels at 15.3 cm per second speed and turning at equal time intervals of 3.27 seconds

The square is 50 cm each.

If we need to keep Romi on the path means to keep the central line sensor on the path then how can we do it. We should not use line sensor in our controller. Its reading can only be used to measure deflection. As the line is only for measuring deflection. In real world there will be no line only trajectory to follow