Core testing

What is being tested	Expected Output	Actual Output
First turn of white path	Follows line	Follows line very closely
Second Turn of white Path	Follow line	Cuts corner of turn
Diagonal straight line	Follow path	Follows very closely
Last corner of with path	Follow path	cuts slight edge of corner but gets back on track quickly

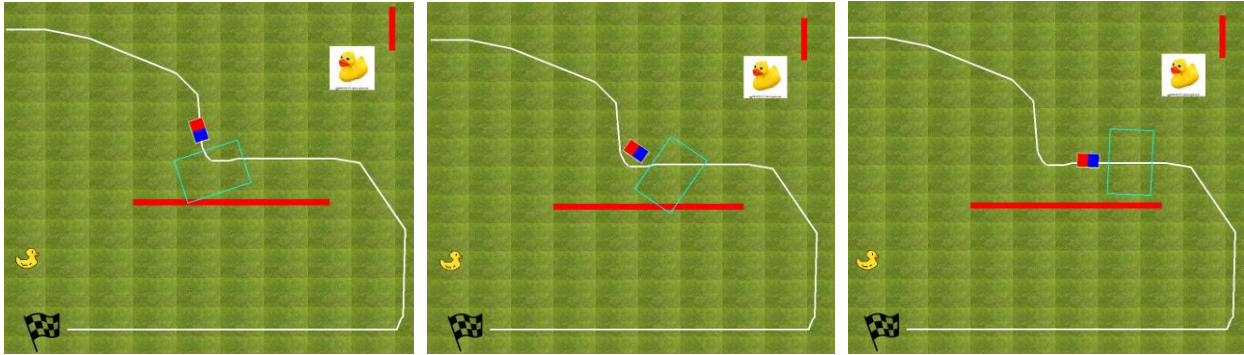| What is being tested	Expected Output	Actual Output
First turn of white path	Follows line	Follows line very closely

After the robot.cpp has started running after the correct method has been selected in the UI the robot starts moving. It follows the with path round the first corner very closely until it has reached the vertical section afterwards.
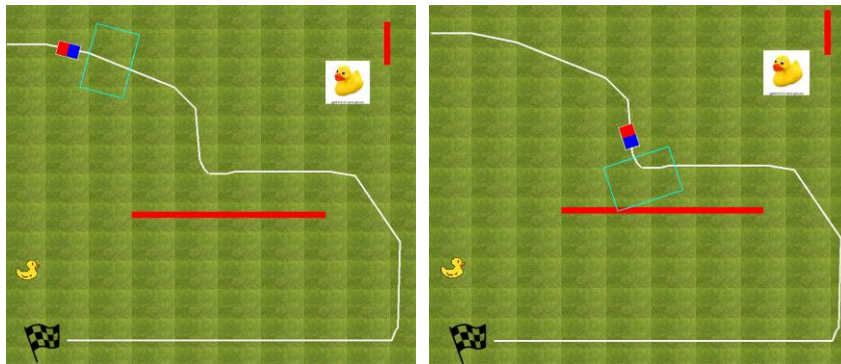
This is the expected outcome for this section.

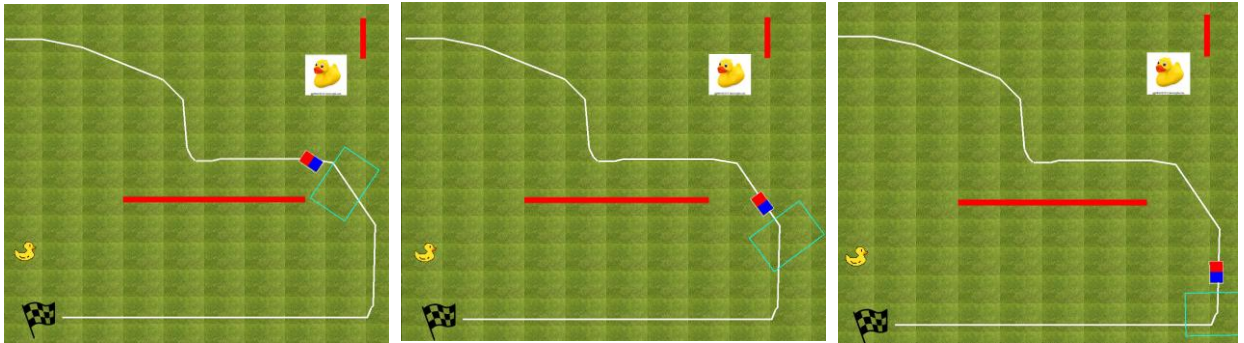| What is being tested	Expected Output	Actual Output
Second Turn of white Path	Follow line	Cuts corner of turn

After the robot has completed the first turn it is in a vertical position and comes into a tight curve. The robot follows this path but slightly cuts the corner, but ends up in the correct position after this minor deviation.

This output is not perfect as it cuts the corner of the path but is so close that it is not very relevant and could be tightened in future iterations.

What is being tested	Expected Output	Actual Output
Diagonal straight line	Follow path	Follows very closely

Once the robot has completed the second turn it approaches a diagonal line which it follows very closely. And results in the robot being vertical afterwards.

This is the expected outcome for this section.

|What is being tested|Expected Output|Actual Output|

|---------------------------|----------------------|-----------------|

|Last corner of with path|Follow path|cuts slight edge of corner but gets back on track quickly|

What is being tested	Expected Output	Actual Output

Last corner of with path	Follow path	cuts slight edge of corner but gets back on track quickly

After the diagonal line the robot has one turn left until completion. This is a tight turn which the robot cuts the slight corner of then is horizontal and runs straight to the finish flag.
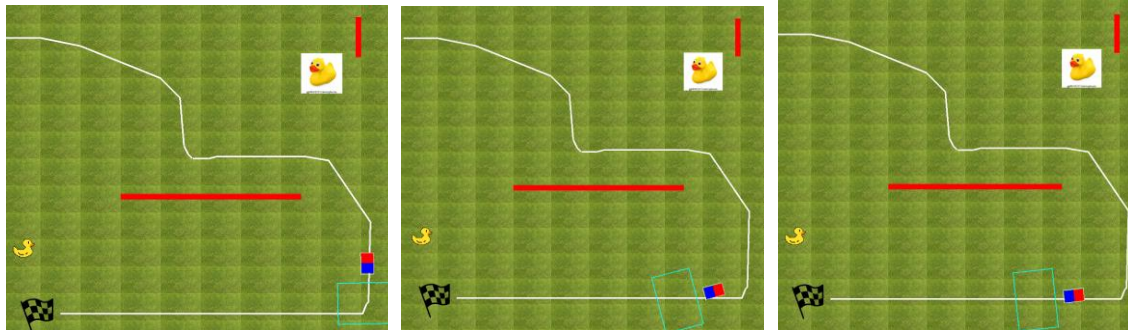
This output is not perfect as it cuts the corner of the path but is so close that it is not very relevant and could be tightened in future iterations. The final straight is the correct outcome for the code.