Last Step:

Complete Maze Navigation

Now that you have successfully programed your robot to follow a straight line, the next step is to combine your knowledge of the infrared sensor with your knowledge of robot maneuvers to achieve complete maze navigation.

* In this step, you must enable your robot to turn left, right, spin around, stop, and have more advanced veering adjustment.
  + For a list of maneuvers see the Arduino Instructional page.
* You should implement either the Left Hand Rule or the Right Hand Rule.
  + This means that when presented with multiple options it will either always turn left or always turn right when the desired direction is available.
    - For more information on the Left and Right Hand Rules, visit the link on the Arduino Instructional page.
* Advanced: after you have gotten your robot able to complete the maze, have it run the maze again and see if you can make it learn the maze by not taking the fake routes for the second time through. Thus it follows the specified Left/Right Hand Rule the first time through, and then runs straight through the maze, only following the correct route a second time.

* + Note, this is not required for achieving credit for your Maze Navigator, just really cool!