



LINE APOSTILE



"He who cannot be a good follower cannot be a good leader."

Test your line following bot against others in a race. But, is it just 'line following'? May be not.

Event description:

Robots per team: One

Length of Event: 5 minutes(Max) **Max participants:** 4

Robot Control: Autonomous





Task:

- The objective of this contest is for a line follower robot to follow a white line on a black background, without losing the line, and navigating turns.
- There are 3 check points and after passing every check point, points will be rewarded.
- The robot to complete the course in the shortest period of time while accurately tracking the course line from start to finish, wins.

<u>Rules:</u>

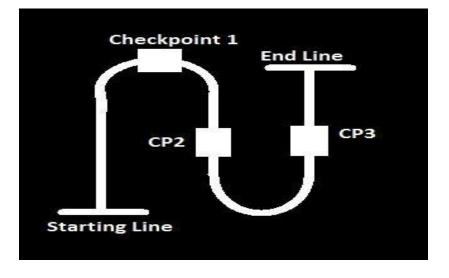
- Task Time: Time is measured from the time the robot crosses the starting line until the time it crosses the finish line. A robot is deemed to have crossed the line when the forward most wheel, track, or leg of the robot contacts or crosses over the line.
- Time Limit: A robot that cannot complete the task in the allotted time shall be disqualified.
- Timekeeping: Time shall be measured by an electronic gate system or by a judge with a stopwatch, based on the availability of equipment. In either case the recorded time shall be final.
- Autonomous Control: Once a robot has crossed the starting line it must remain fully autonomous, or it will be disqualified.
- Losing the Line: Two attempts will be given to any bot that loses the line course, bot must acquire the previous check point it has already traversed.
- Use of microcontroller is not compulsory.

Sample Arena:

NOTE: Actual arena can be modified on the spot.







Judging criteria:

The team who completes the task or the one who'll crosses maximum check points in minimum time, will be considered as winner.

Event Co-Ordinator:

- **Chief :** Mohit Jain(8432667745)
- **Other**: Vishnu Saini (9460423502)

Dinesh Suthar (9784285774) Nancy Singh (8696544404) Ishita Garg (8952060696)

Keshav Soni (7597920387)

Meenakshi Gaur (8963063747)