Good morning, sir, we are the group sentinels. First, I am going to explain the mechanical design and the physical structure of the robot. These are the main three views of the robot side, bottom, and front. When we look at the overall design, we are going with a two-stage design for easy wire management and to gain more surface area to place all the modules. In the bottom layer, we are placing the battery and two motors which are heavyset and will improve the center of gravity by moving the cog near to the ground, and the IR sensor array which is used to identify the line in the bottom layer. Also, there are 6 TOF laser ranging sensors to identify the front of the robot also there is another TOF sensor in the middle of the arm to identify the front of the robot. This means we are using a total number of 7 TOF sensors to identify the surroundings. In the middle front of the robot connecting the two bottom and top layers, the robot arm is placed. it has two parallel grabbing plates to ensure the grip of the arm. Furthermore, there is one TOF laser ranging sensor and an RGB color sensor to identify the box and its color. The arm can be tilted up and down about 20 degrees to prevent contact of the box with the ground. In the top layer of the robot, there will be all the electronics of the robot which are the lightest which will also improve the stability of the robot. Even though it is a simple design, it fulfills all requirements to complete the task. That is all about the mechanical structure of the robot. Now I will hand it over to Nadil to explain each sub-task.