Task 1: <https://www.tinkercad.com/things/4UnIH0TF5g3-robocon-task-1/editel?returnTo=https%3A%2F%2Fwww.tinkercad.com%2Fdashboard%2Fdesigns%2Fcircuits&sharecode=K746VNWLeeRwpkWr61BBScOxVzq1nmHCPUIq0z_ShC4>

Task 2 (main): <https://www.tinkercad.com/things/5qdQIJD1jPO-robocon-task-2-main/editel?returnTo=https%3A%2F%2Fwww.tinkercad.com%2Fdashboard%2Fdesigns%2Fcircuits&sharecode=Uhb6nnSGe8g67idfO9prSIvRhQvHtlUBW3yvi9fQs-A>

Task 2 (brownie): <https://www.tinkercad.com/things/bDXzDNyjo02-robocon-task-2/editel?returnTo=https%3A%2F%2Fwww.tinkercad.com%2Fdashboard%2Fdesigns%2Fcircuits&sharecode=oBVQiSE5Wi6eu1bzySQ4J14QQwC-781wzrIel8F3r-E>

In second question I placed three sensors. One measures the distance in front of the bot while other two measures the distances sideways (Left and Right). I placed two motors each of which will control a wheel of the bot (considering that the bot has only two wheels). The bot will move forward if there is no obstacle within 15 centimeters of the bot while it will apply breaks after 15 centimeters (By reversing its motion). [The application of the bot is according to the BROWNIE task and not the main task which was given because the main task contains some functions which are not to be done by an obstacle avoidance bot].

For turning of bot to right on the spot where it stands, I reversed its right wheel and pushed left wheel forward which will rotate the bot towards right on the very place it stands. Same was done for left side rotation as well.