

Welcome to NB theme!



Rulebook ›

Task 0 ›

Task 1 ›

**Task 2** ✓

2A - Develop Ball Tracking Algorithm

2B - Generate Maze in CoppeliaSim  
with Remote API

Task 3 ›

Task 4 ›

Task 5 ›

Practice Task

Instructions for Task 6

Task 6 Scene Details &lt;

Coding Standard

Git and GitHub

Live Session 1 - 24th October 2020

Live Session 2 - 21st November 2020

Live Session 3 - 12th December 2020

Live Session 4 - 10th January 2021

Changelog



## eYRC 2020-21: Nirikshak Bot (NB)

## Task 2

[ Last Updated on: 02nd November 2020, 16:44 Hrs ]

Welcome to **Task 2** of **Nirikshak Bot**.

The aim of this task is to **adapt, improvise and build** on the concepts of Image processing, Algorithm Building and Robotic Simulation learnt in Task 1.

This task is divided into **two** parts:

- **(1) Task 2A**
  - This task is based on **Image Processing** using **Vision Sensors in CoppeliaSim**.
  - Teams should apply the concepts learnt in **Task 1A** and **1B** and build a Python Remote API file to find the correct **Shape, Color, Centroid X and Centroid Y** of the ball(s) in the dynamic CoppeliaSim scene using a Vision Sensor.
- **(2) Task 2B**
  - This task is based on **maze generation in CoppeliaSim** using the **output of Task 1B**.
  - Teams should use **python remote API** to **transmit the encoded maze array** (output of task 1b) to a **Lua script** in CoppeliaSim scene to **generate walls of the maze**.

ALL THE BEST !!