a) What are the parameters that should be considered while calculating maximum angle of inclination in Two wheeled self-balancing robots (TWSBR)?

- Center of gravity (The lower it is the easier it is to balance therefore the inclination will be less)
- Shape and structure of the robot (distribution of mass should be even)
- Height of the robot
- Alignment of center of gravity with center of mass

b) What is the core concept of the Two wheeled self-balancing robots (TWSBR).

- Balancing pendulum/ inverted pendulum

c) What is the additional thing/component that you can add to make it unique and explain the same by giving its proof of concept.

Usin the data from both lidar and 3d depth sinsing camera.