The mechanical design of the prototype is made in small dimensions which meets the rules of the competition.

it contains holes at the bottom for the ir sensors which are used to detect the circle and holes in the front for the ultrasonic sensor and the ir sensor which are used to detect the opposite robot.

At the front of the design there is a slider which can lift the opposite robot at the moment of collision which will make it easier for the robot to carry it out of the circle.

We are using two high torque geared dc motors which we be easier in control than using four motors in the back of the robot letting the front of the robot in friction with the ground to make the robot harder to be pushed and keep the front of the robot at lower level than its opponent and this will make the lifting of the opposite robot easier.