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Github : https://github.com/dxg397/EECS-476/PS2

Approach:

Firstly, I added two variables left_offset and right_offset in addition to the middle one to set the range of the lidar alarm.

Then I created a variable to keep a check on the ping which returns "DANGER Will Devansh!!".

Then I created a loop that checks every ping and find the ping distance, if the ping distance if less than the min_safe_distance, then it sets the unsafe_ping variable to TRUE or else I assumed it's a duplicate ping or pseudo ping.

Observations:

1. Sometimes the robot enters a corner surrounded three ways by walls and it keeps rotating more than once but ultimately comes out of the corner.

2. I purposely changed the unsafe_ping Boolean variable to false even after coming out of the loop just make it safe.