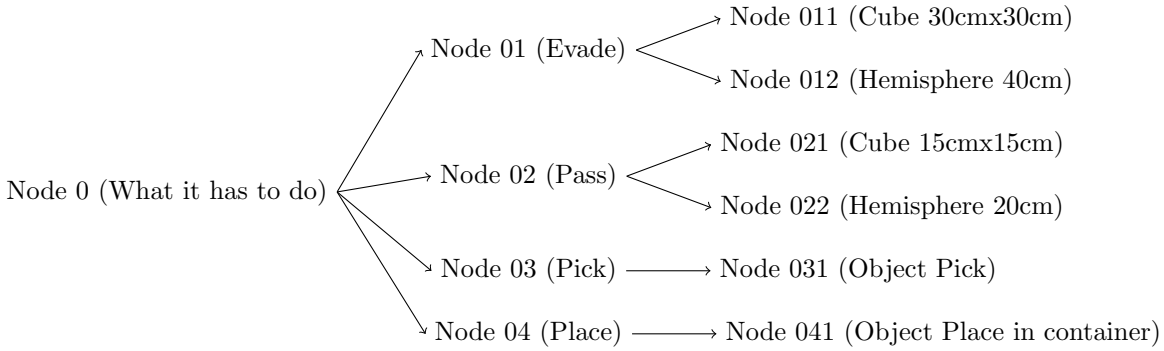
Detecting Block
Using the sensor to identify two types of blocks (A, B) employing trigonometry and other suitable methods to determine their size and categorize them.

- **Pass**: Confirming successful identification and categorization.
- **Evade**: Navigating around identified blocks.

Detecting Crater
Utilizing the sensor to recognize two types of craters (A, B) employing trigonometry and other suitable methods to determine their size and categorize them.

- **Pass**: Confirming successful identification and categorization.
- **Evade**: Navigating around identified craters.

After everypass('everypass', is defined as a movement of the rover in the direction of it's view, and is determined by the movemnet it makes, in any manner.), the rover's brain will pass through the given structure and decide it's next move.



Major Details:
Node 3: The camera palced on the rover will effectively calculate the shape and dimension of the object to pick and adjust the maximum distance of the seperation between hands by 1.1d for the object to get picked. The minimum close range is 0.9d for it not to get damaged. The hand will pick the object from the curved edges, and palce it's hand between them for the torque to act less and with less force it'll get picked. Here, d is the diameter of the object to be picked (it can be hard encoded into the machinery as well.)