EDGE-SENSING-BOT

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Circuit connections Are Almost Same As of the Line following BoT...

Code is Also Almost Same with A function Named As go_Back() Added.

the function is trigred at the deadend!

```cpp
else if (l_ir_input == 1 && r_ir_input == 1) {
    // Both sensors detect edge → Go back and turn right (escape)
    go_back();
    delay(1000);    // Move backward for 1 second
    stop();
    go_right();     // Then turn right to get back on surface
    delay(500);
}
```

```cpp
void go_back() {
    digitalWrite(rmf, LOW);
    digitalWrite(rmb, HIGH);
    digitalWrite(lmf, LOW);
    digitalWrite(lmb, HIGH);
}
```

→ IN2 will get high to move right side motor Anti clock wise

IN 4 would get this

Same for left side motor