

After Match

- ☐ Reset climb and latch (including ratchets and pipe insulation)
- ☐ Zero the dart and the tongue
- ☐ Charge driver station
- ☐ Charge GoPro
- ☐ Charge match battery
- ☐ Hang up bumper

Maintenance

- ☐ Electrical Connections: Roborio, Radio, VRM, PDB, Main Breaker, Encoders, CAN Bus, Limelight, USB Camera
- ☐ Tighten Bolts: Tongue, Dart, Wheels, etc.
- ☐ Lubricate: Climb, Drive Train
- ☐ Scan for wear: Frame, Treads, Bumpers, etc.
- ☐ Tension Chains
- ☐ Systems Check and Communications Test

Pre-Match

- ☐ Confirm correct bumpers are mounted
- ☐ Verify and then swap in the next fully charged battery
- ☐ Secure battery with bungee
- ☐ Ensure back Sponsor Panel is mounted
- ☐ Ensure clip-on rocket is mounted
- ☐ Replace tongue tape
- ☐ Ensure side electrical panels are mounted
- ☐ Ensure pipe insulation is mounted to the top of both struts
- ☐ Driver Station is ready: Laptop is charged, GoPro is charged and has its microSD card, two joysticks, one gamepad

MATCH: DRIVER STATION

(Eddy and Felipe)

- ☐ Mount team control panel to the driver station
- ☐ Power on the laptop
- ☐ Plug in the dock charger
- ☐ Plug in field ethernet connection
- ☐ Restart the driver station software
- ☐ Verify all controllers' axes are zeroed and buttons are displaying the correct inputs
- ☐ Turn on the GoPro and Start the recording
- ☐ Verify connection to the robot
- ☐ Verify camera streams are displaying properly
- ☐ Select Auto routine

MATCH: FIELD (Jeff and Sam)

- ☐ Check wingnuts (bumper)
- ☐ Place robot for planned autonomous
- ☐ Place hatch panel onto tongue
- ☐ Wind hatch tongue and hold tongue towards the robot
- ☐ Power on the robot
- ☐ Check Encoder LEDs
- ☐ Check Roborio, Radio, and Limelight
- ☐ Confirm Cargo Ship (Null Hatch Panel) and remove rocket clip
- ☐ Scan the robot for loose tools
- ☐ Confirm communication to driver station
- ☐ Confirm camera streams
- ☐ Check USB Camera position
- ☐ Select Auto routine