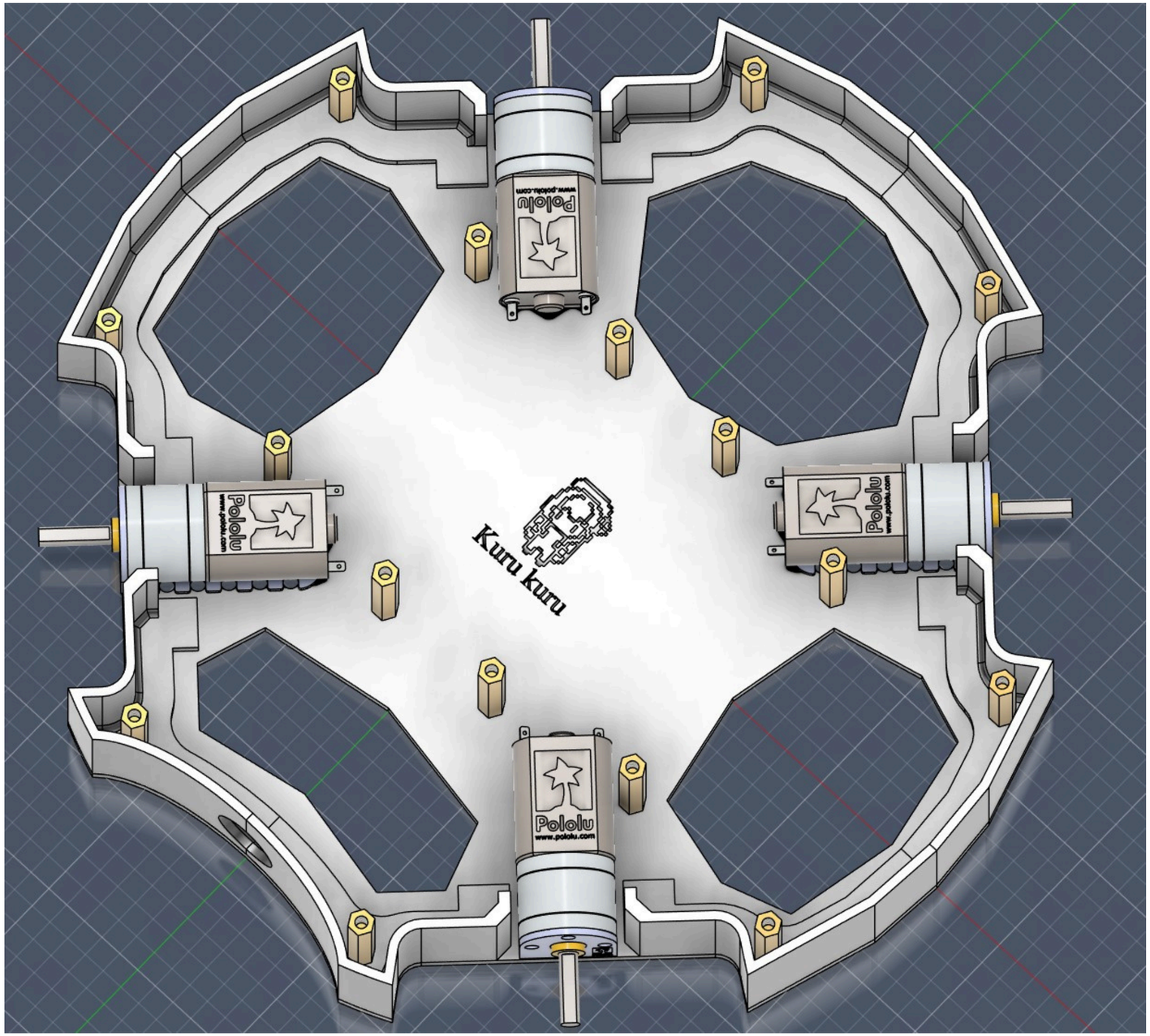
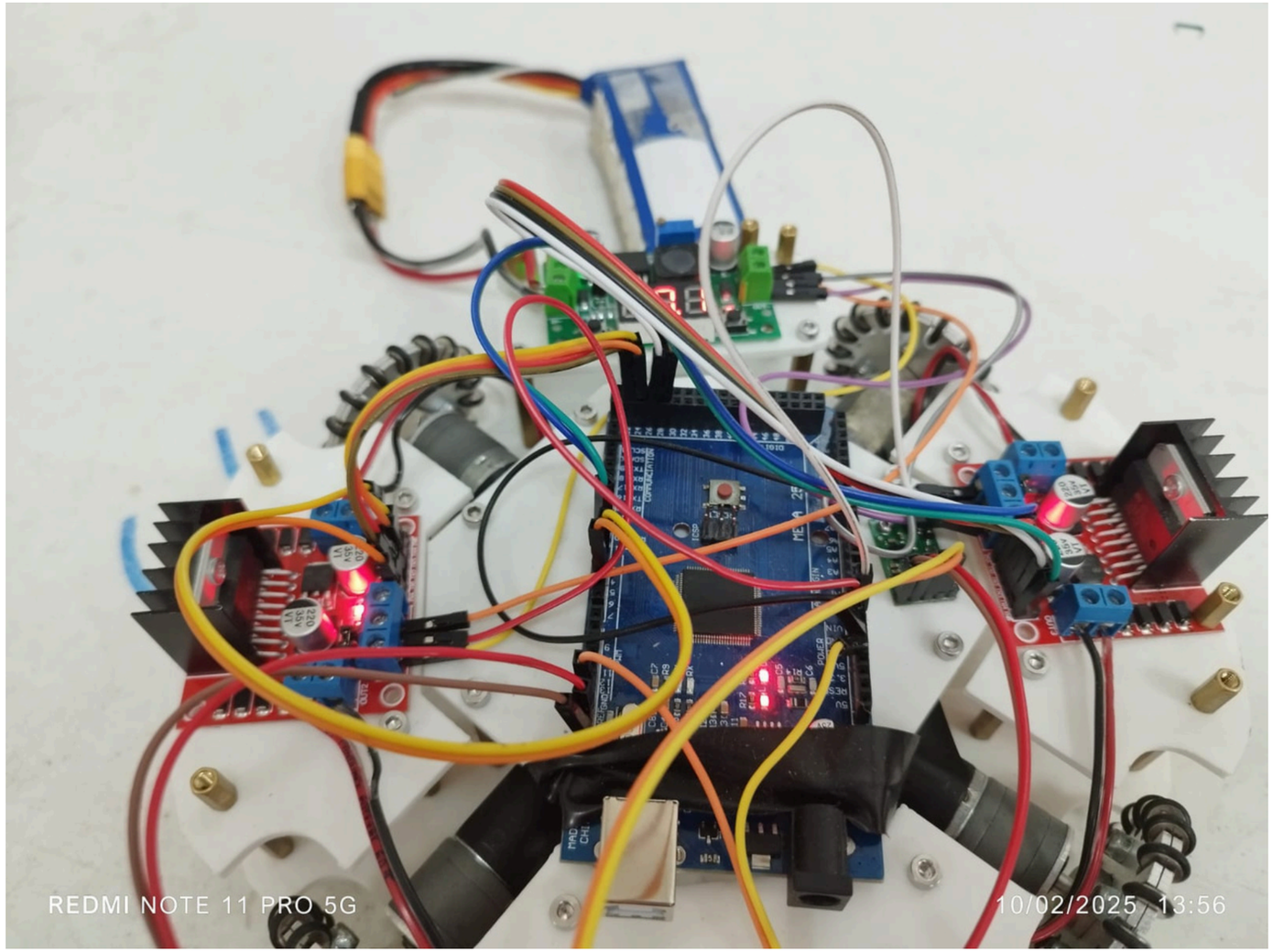
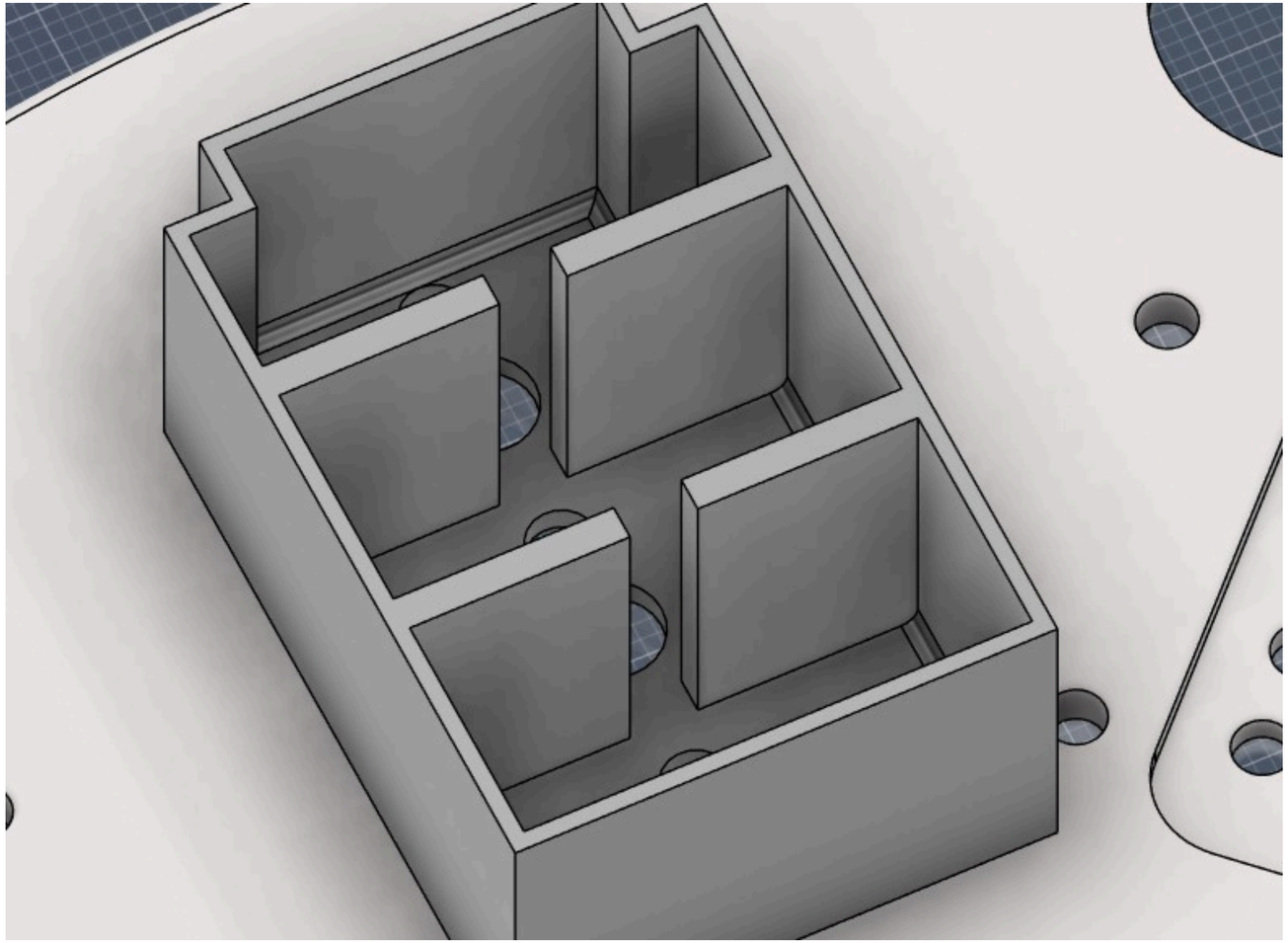


this design was created so that the walls can be easily uncoupled and the robot is modular.

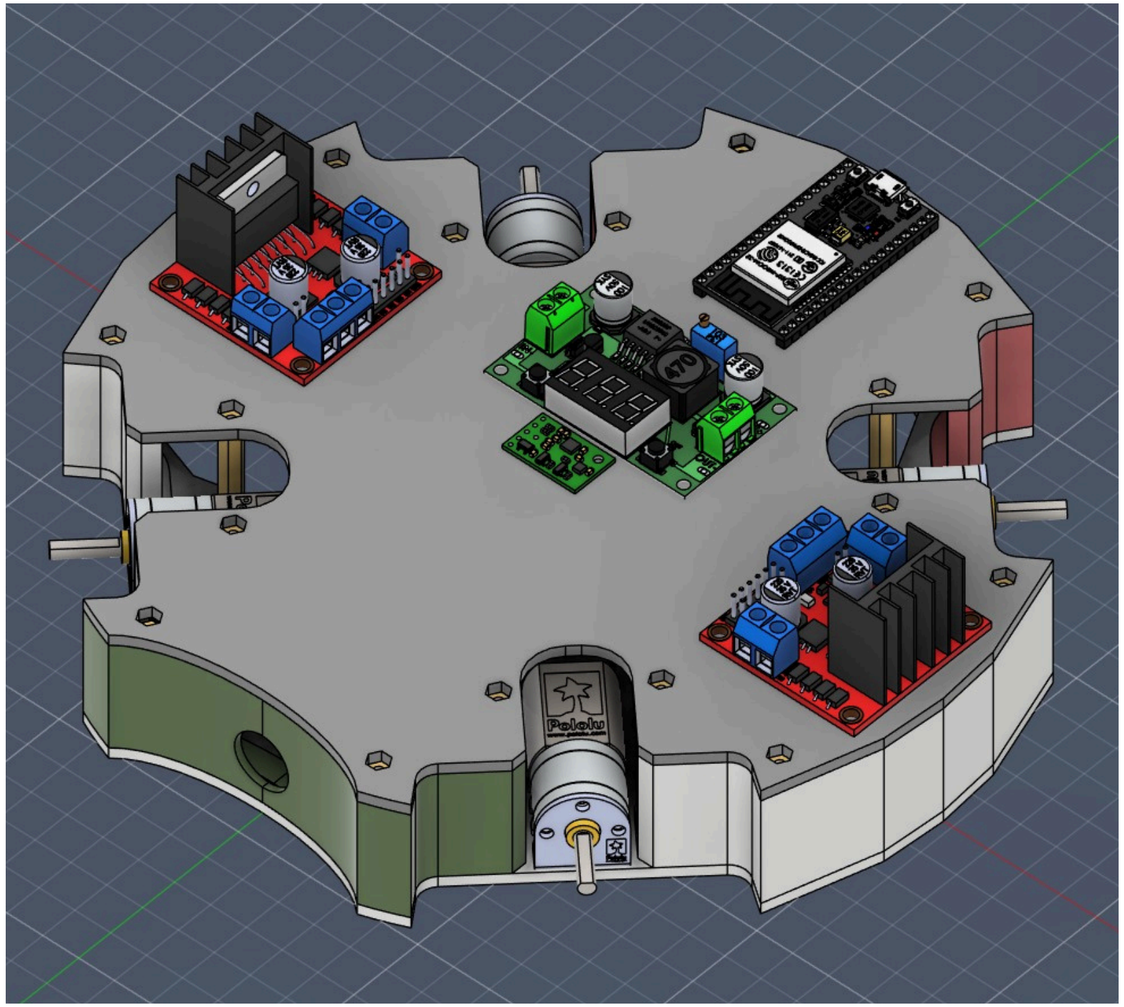
These were the connections the robot had before having the pcb's.

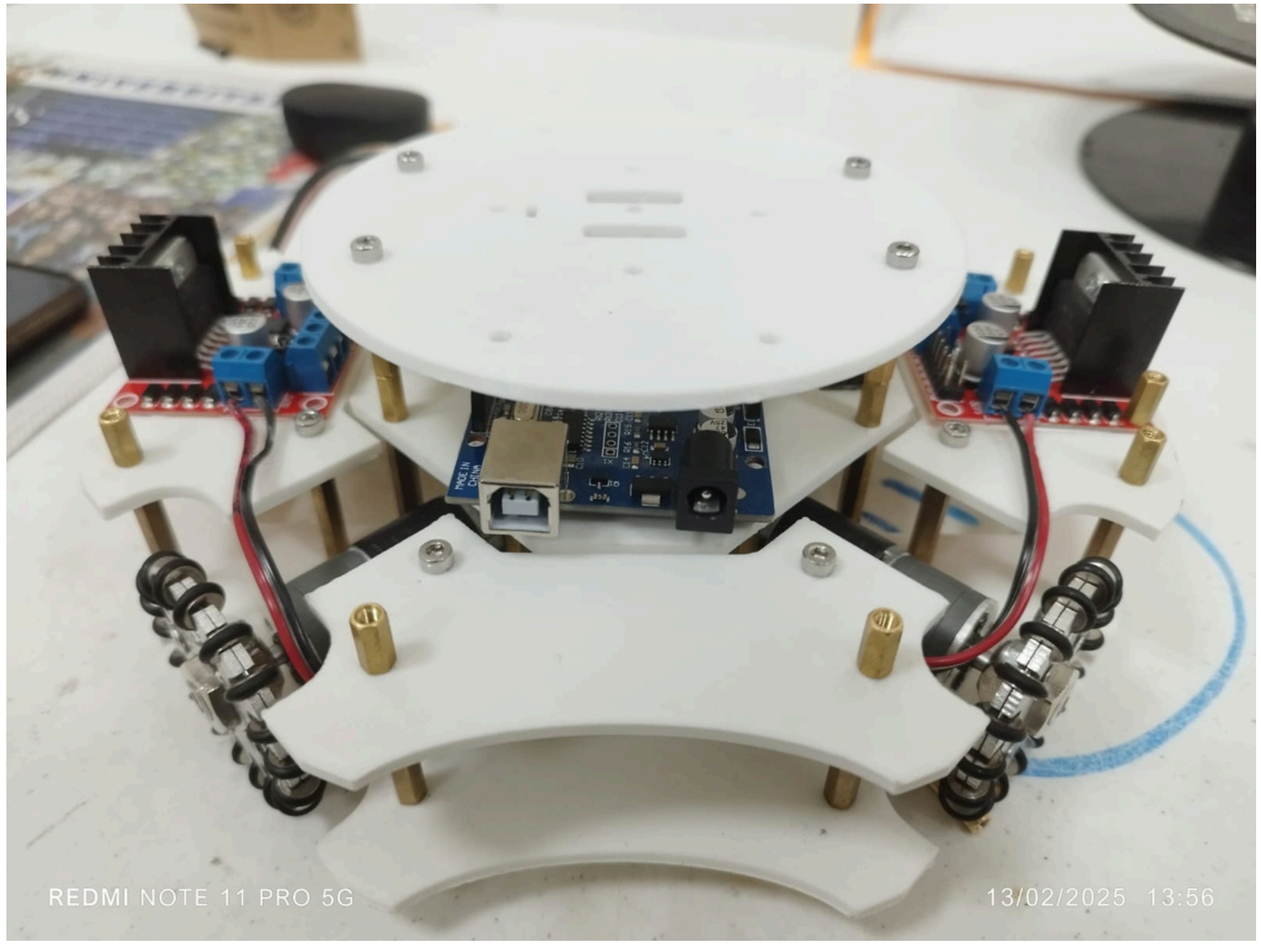




This was the first design to use ldr without a pcb.

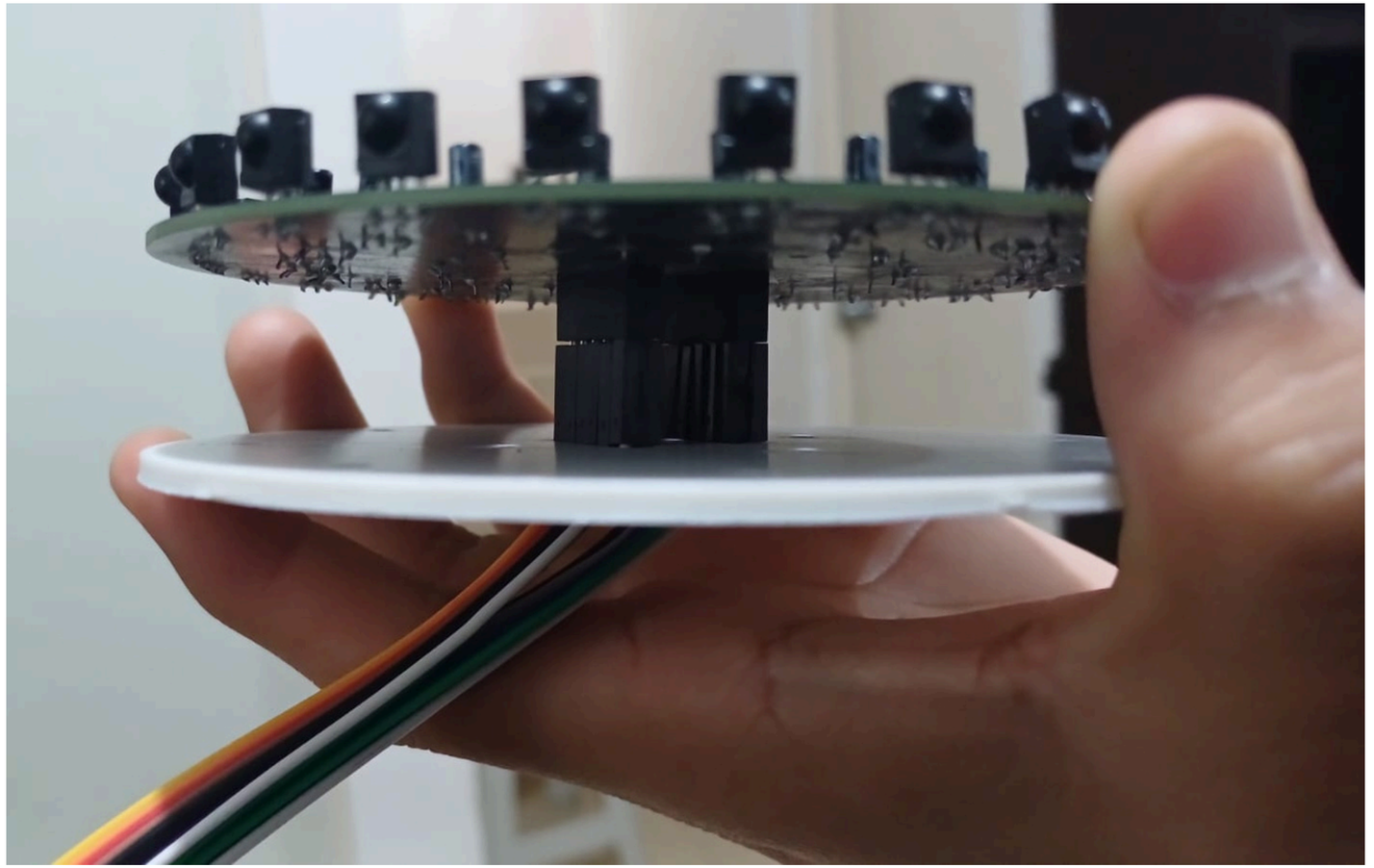
This is the design contemplating that we would use pcbs and we had the idea of implementing a kicker but for economic reasons we could not implement it.

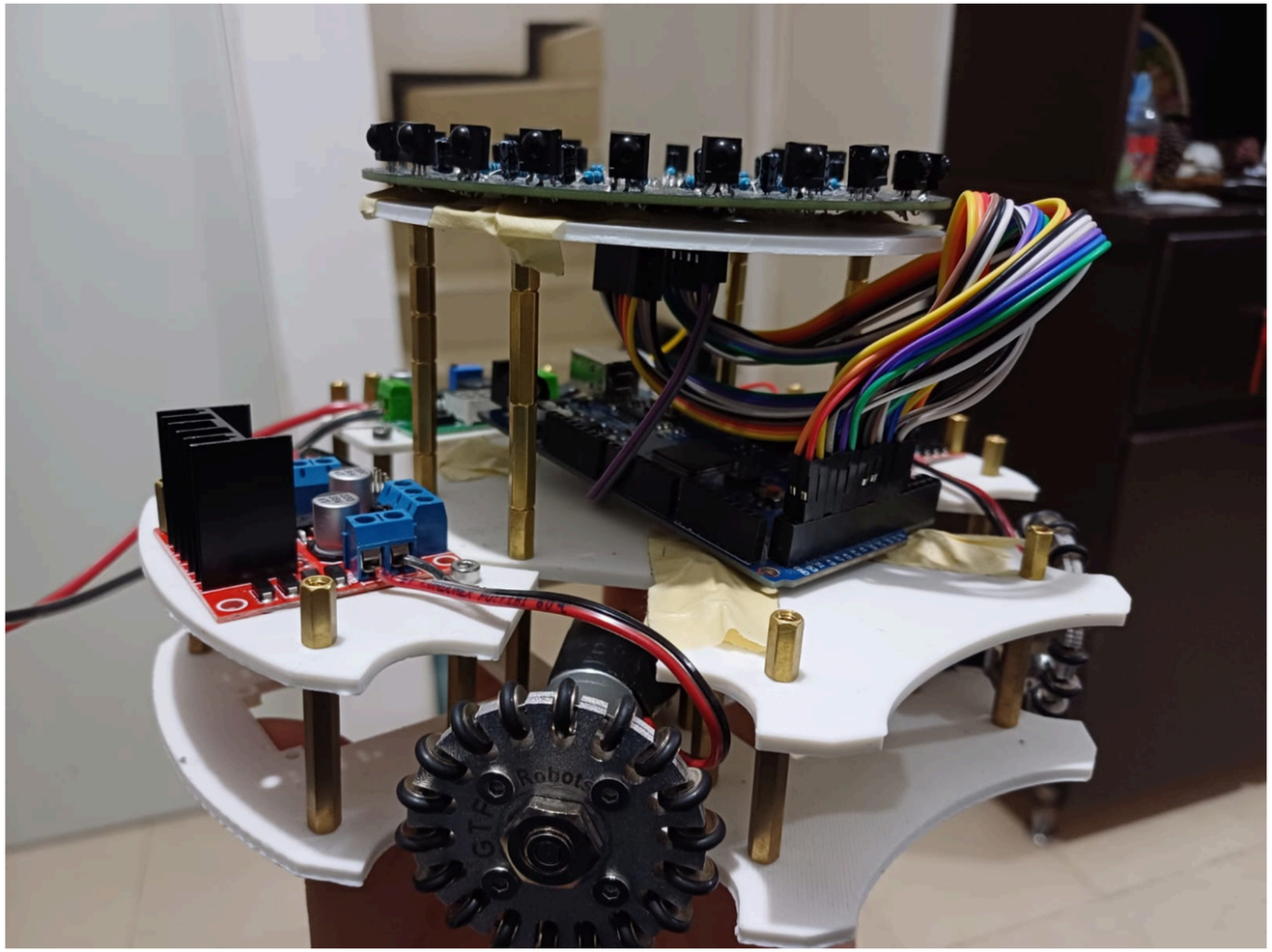




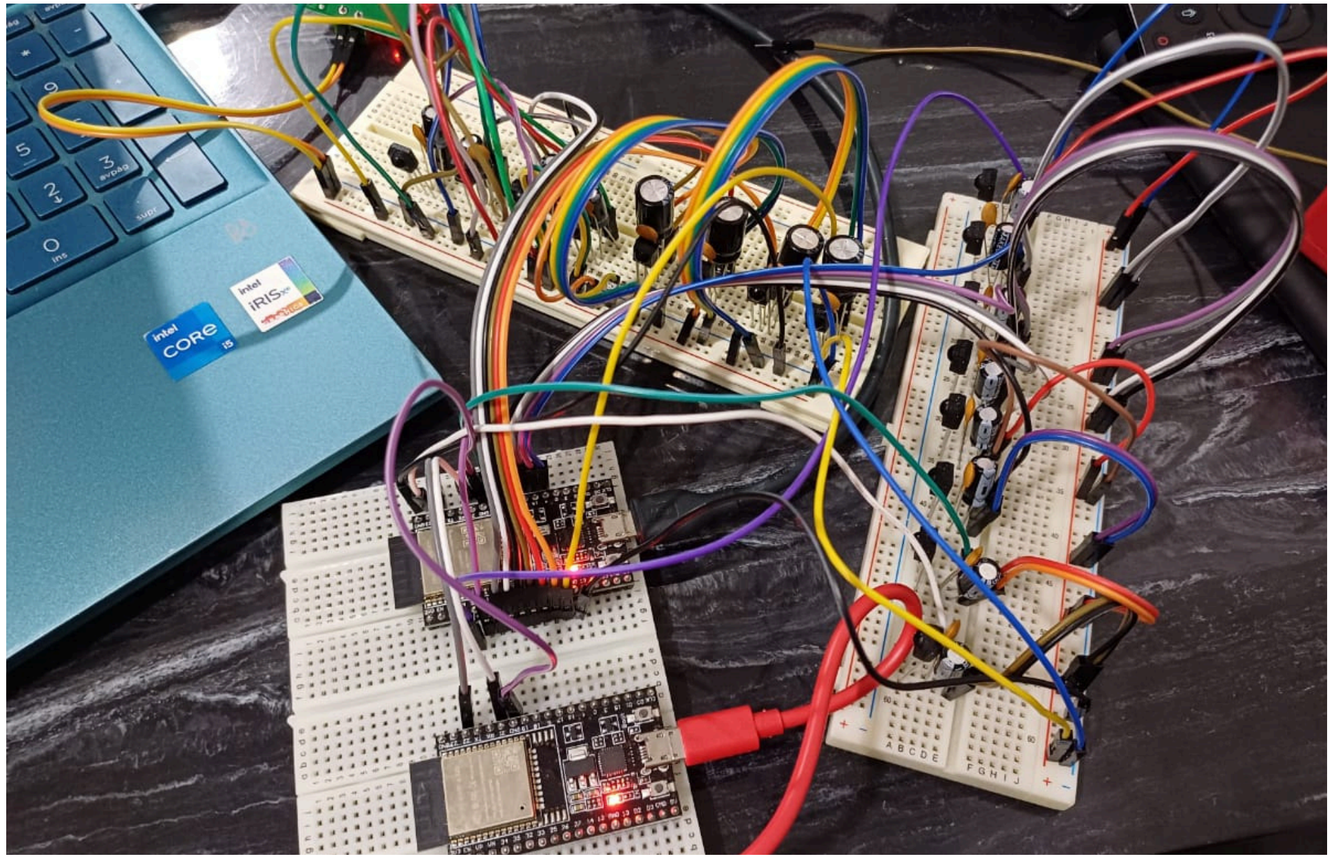
here the chassis had already been printed and the components had been ordered

When we had the plates ready to go we started testing to see how they would work.



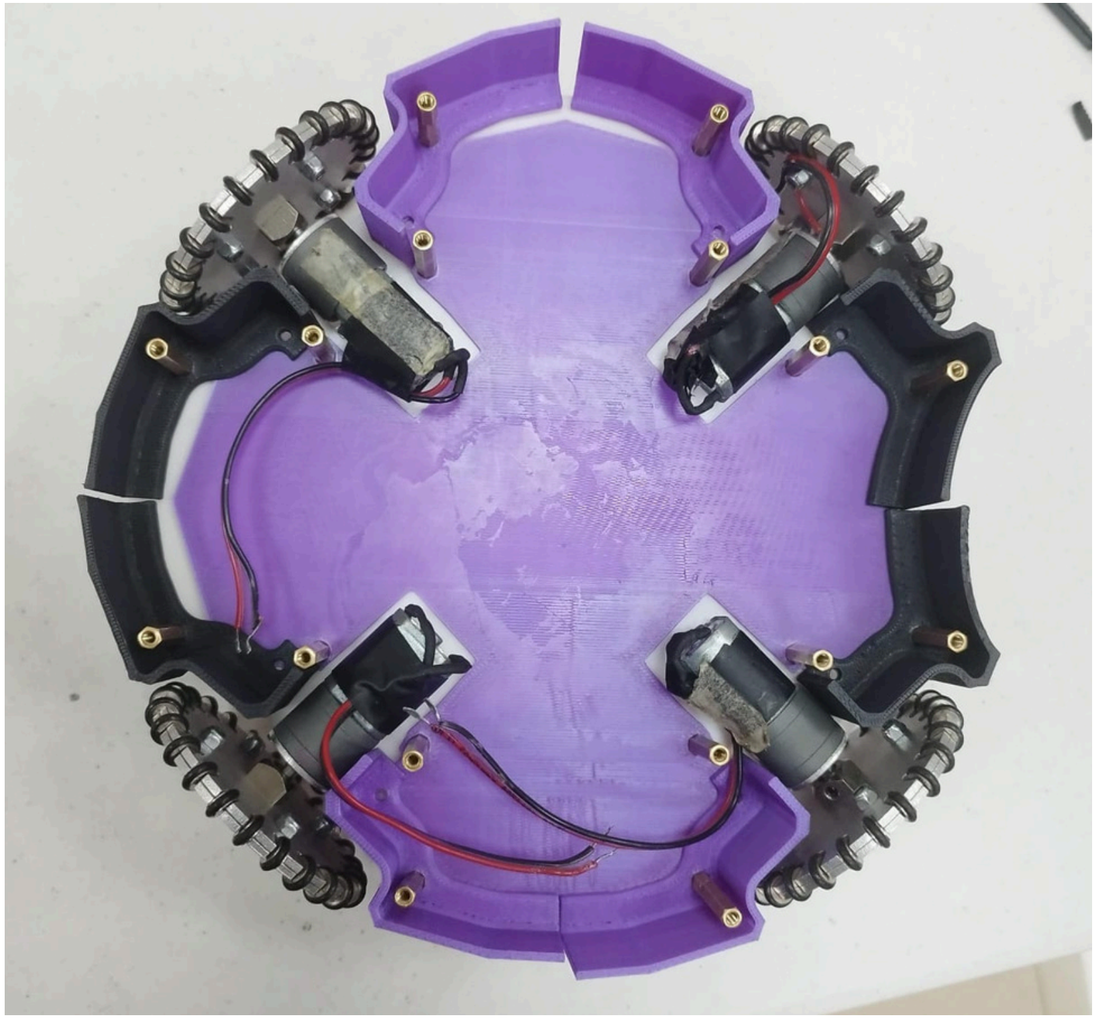


We arranged all the parts of the robot and the ir board was already working.

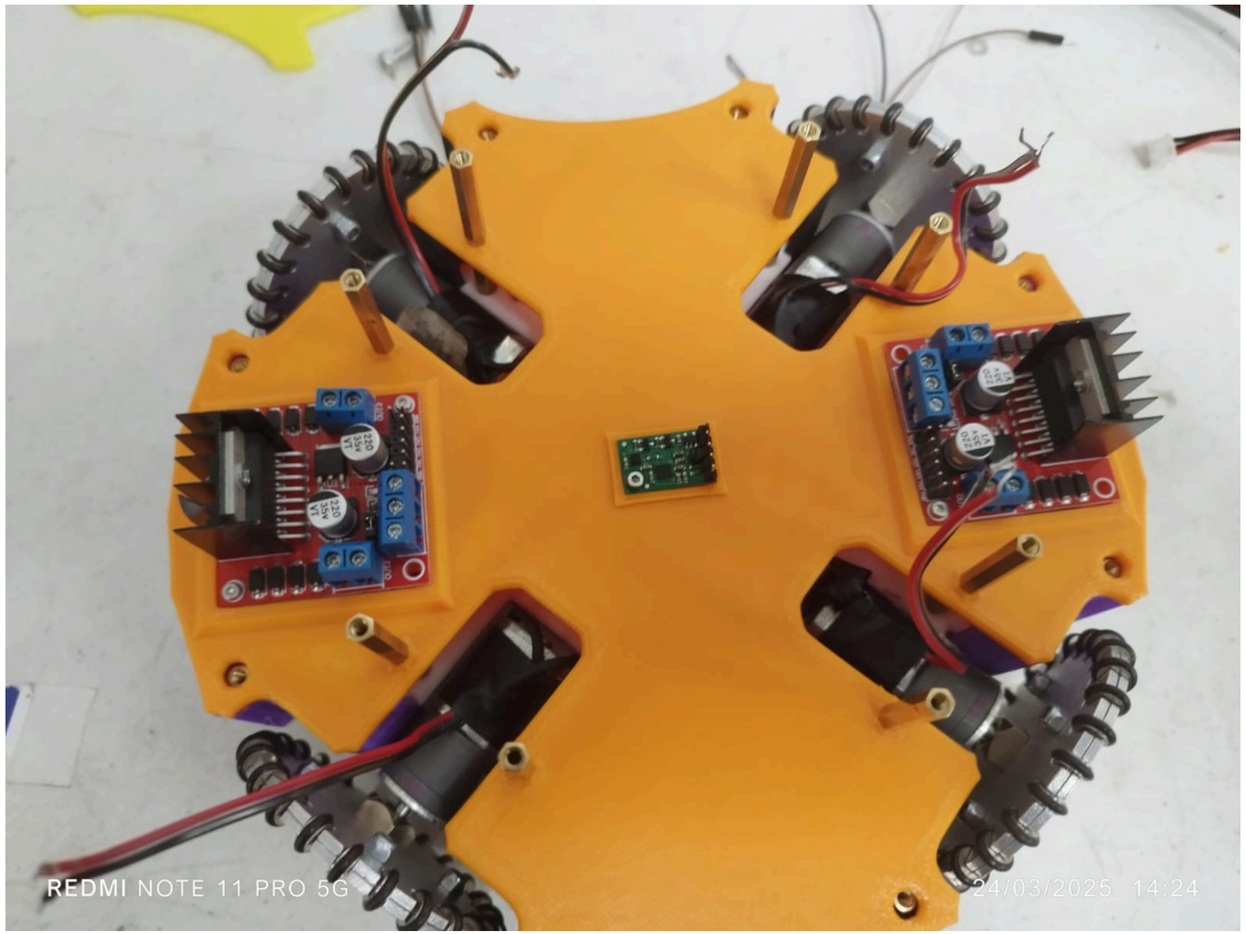


We made the schematic to test the operation of the second board, when it worked we tested the serial connection and ordered the board.

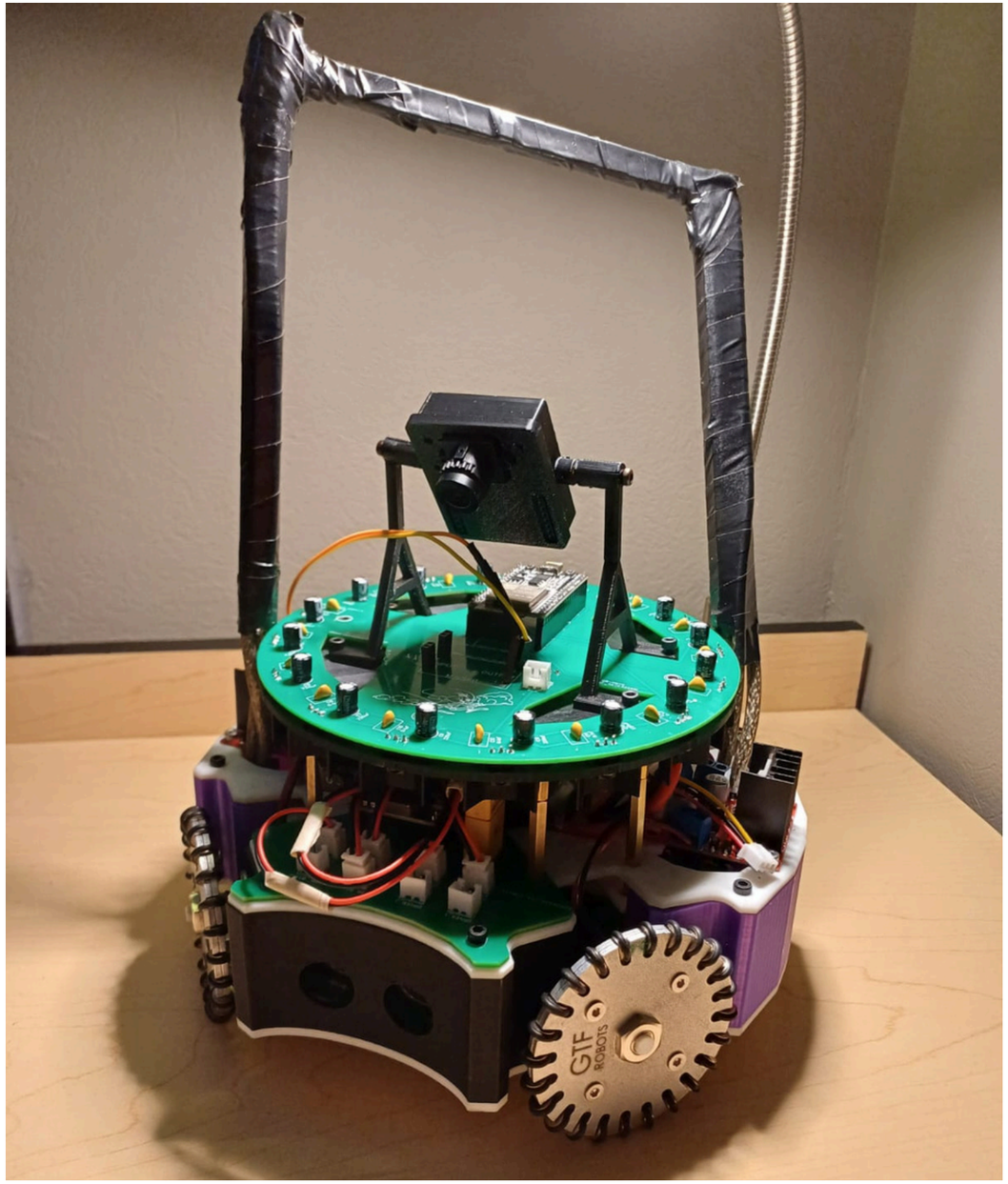
We made 3d printed plates to test sizes and shapes.



This is the final 3d print design



This is the second part of the design with the following components



This is the final design with the pcb and the open mv