

Engineering Notebook

FTC 7347

October 31, 2014

Matt Iverson

2014-09-16

Brainstorming

This week, I calculated the space we'd need for a scissor lift / conveyor belt mechanism.	The mechanism will fit and reach high enough, but it'll take up a lot of space.
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I measured our team's conveyor belt to be 2.5 inches thick. Our robot can be up to 18 inches tall, so we can fit up to 7 layers of the conveyor belt on our robot. We'll need about 2.5 inches on each side of the conveyor belt for tubing to move balls between belt layers, so the belt can be up to 13 inches long. 13 inches at a 45 degree angle is approximately 9.2 inches up and to the side, meaning our scissor lift could reach up to 64 inches (163 cm). This is well above the top of the center goal (120 cm), but I think the system will likely collapse under its own weight at that height.

Nick Vosseteig

2014-09-17

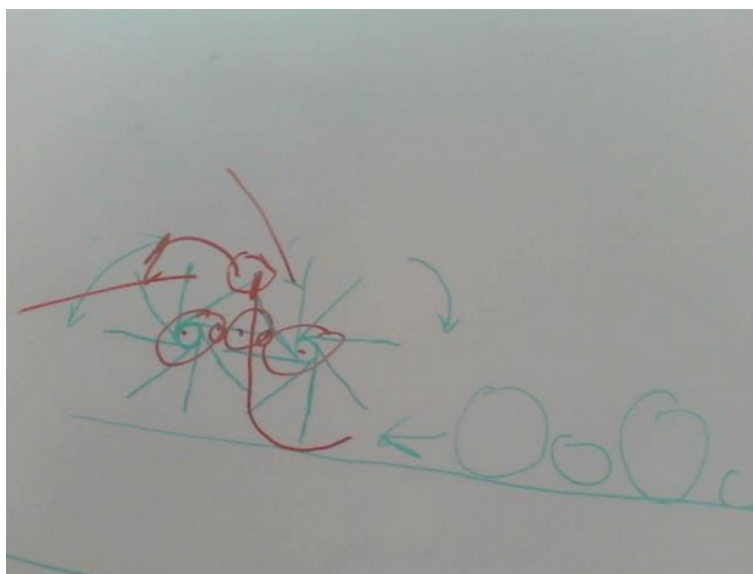
Brainstorming, Designing, and Promoting FTC

This week, the team and I worked together to brainstorm possible ideas for the intake device, the lifter, and the scorer. We also did some calculations and strategic planning.

Reflections (how it went): Overall, it went very well. We successfully came up with a design for the intake device and plan to begin building it next week. We have some possible designs for the lifter and scorer as well, but we are not completely decided and plan to do some tests and calculations to determine what the best method will be.

The main challenge with the brainstorming is trying to lift two different sized balls the maximum of 120 centimeters. It's hard to design an intake device that can pick up both the small and large ball. We also determined that it is most efficient to just pick up all the balls and put them randomly into the tubes instead of trying to get one small, then one large, as this is too challenging and not worth trying to build something to sort the balls and add them to the tube separately. The next problem was not picking up too many balls at once, which we have still not found a definite solution for. We are considering using sensors, but we don't have this incorporated into the design yet.

Here is a picture of the mechanism that we plan to build next week:



The spinners represent brushes, but we are going to build the device with only one brush and test if it will work that way. The one-brush design will only use the front brush and have something to shove the ball up against (represented by the red line in between the two brushes).

Ben Trout

2014-09-19

Brainstorming, Designing, and Promoting FTC

Brainstorming	We started our brainstorming by making three subsystems for scoring blocks: Intake, Lifter, and Scorer. We had a bunch of designs down and ideas flowing. As a team we we're able to list pros and cons of all the designs mentioned and narrowed it down to just a few quality designs.
Designing	Once we had our ideas pinpointed that we thought would be best for accomplishing the challenge we started to design different components of the robot. Me, Nick, and Alex mainly focused on the intake method of picking up balls.
Promoting FTC and FIRST	I went to a lego robotics meeting with my FRC team for recruiting Lego Robotics coaches for the FLL league at liberty that we're starting up. We wanted to promote all three levels of FIRST. We had old lego robots for demo, I brought a ball shooting FTC robot I built and my FRC team brought their worlds robot from last year. We demo'd all the robots and got the kids exited for robotics, hopefully they will move up in the FIRST levels and be on the Liberty FTC team in the future.

Brainstorming

Ways to play the game:

- Tip rolling goal onto ramp. Shuttle balls up and down ramp
- Grab rolling goal and drive around with it putting balls in
- Put balls into center goal

Subsystems:

- Intake
 - scooper

- rotating brush
- suction
- rotating wheels

- Lifter

Subsystems:

- Intake

- scooper
- rotating brush
- conveyor belt
- suction
- rotating wheels

- Lifter

- batched
- continuous feed

- Scorer

- active dumper
- passive dumper

- Goal attachment

- claw

- Drive base

Lifter/Scorer:

Trio of Archimedes Screw

Conveyer belt Tri belt Pulley system

Guided launcher mechanism

Ball sorter

Scissor lift with conveyer belt to bring balls up

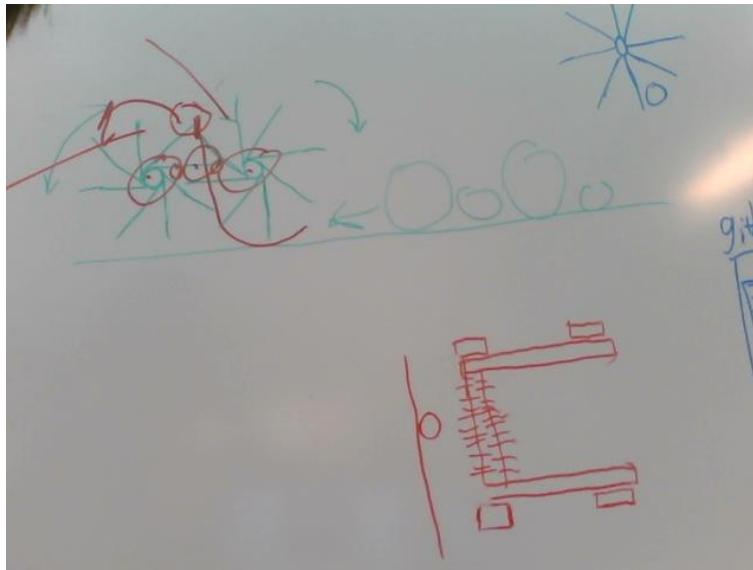
Spring Shot with guided tube

Pulley system

surgical tubing sling shot with guided tube

Designing

As a team we finalized on rotating brushes to intake the balls, a surgical tubing sling shot with a guided tube into the goals, and a passive dumper. Our main idea for scoring is using claws to attach to the base of the goal and carry it around with as we launch balls up a tube and deflected into the goal. We have rotating brushes that intake the balls into a slingshot that launches the balls into a guided tube that is extended and retracted by a pulley system. The only part of our brainstorming that we have designed is our intake:



The balls flow under our robot where one rotating brush brushes up a wall bring the balls up into the robot and deflected onto a ramp that leads the balls into the slingshot. The odds of surpassing the five ball limit is low so we aren't going to incorporate a sensor yet. We did a lot of calculations like how many balls we'll pick up per second, size of balls, and if different ideas like a scissor lift will fit in our Robot. I wasn't in charge of calculating, but other team members like David and Matthew were.

Promoting FIRST

At the meeting put on by my FRC team our main goal was to get Lego Robotics coaches for the starting lego robotics program at Liberty. We want to get young students excited for robotics and mainly Lego robotics. But we don't want these kids robotics to end with FLL. We want to start their robotics program early and keep them going through the levels of FIRST so that when they get to FRC they are used to robotics and accustomed. The FRC team brought that robot and demo'd it and I brought a small FTC robot I made to demo for the kids. We had all three levels of FIRST robots present to get the kids and parents excited for Robotics.



Alex Iverson

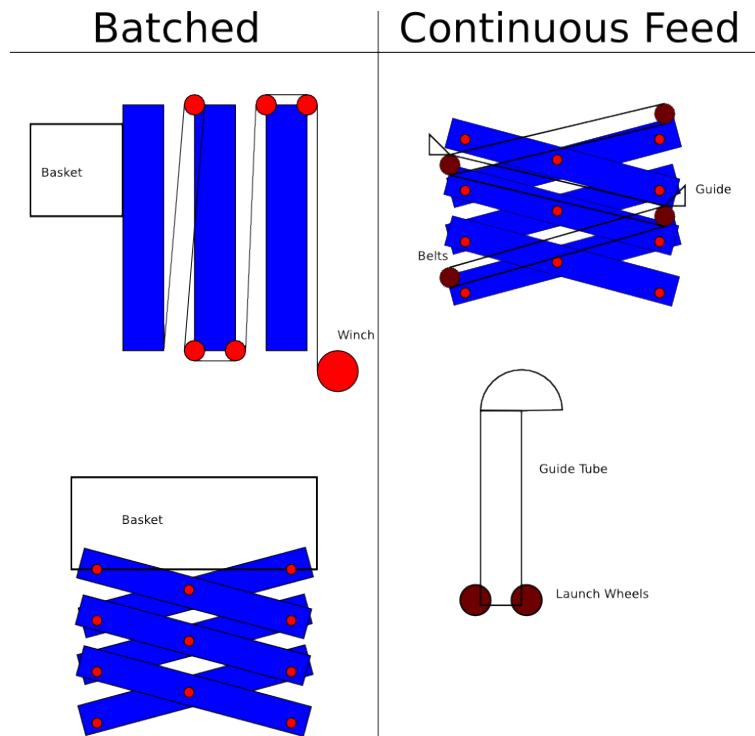
2014-09-22

Strategizing and Brainstorming

I worked on Identifying ways to play the game.	I think we were fairly thorough. I do not anticipate seeing any major strategy elements at the tournaments we have not anticipated. I do, however, expect to encounter a combination or variation that we have not considered.
I helped brainstorm types of players we could build.	I would have liked to have come up with more possibilities, but I can not think of anything to add. However, it is taking a long time to analyze the ideas we have because some of the team members need to be trained how to do so; Having too many more ideas may take too much time.

The first thing we did was try to identify what interactions with the field elements were involved in playing the game. Then we looked at how these interactions could be combined into strategies.

The first major challenge was to organize the brainstorming. Because I have more experience with designing for the FIRST competitions, I led the effort. I had difficulty conveying the distinctions between subsystems and mechanisms for the purposes of strategizing. Subsystems are categories for how the robots can interact with the field and gameplay elements, for example, a batched scorer versus a continuous feed scorer, or a rolling goal pusher versus a rolling goal grapppler. They are relevant to strategy because those distinctions affect what the robots are able to do on the field. A mechanism is an implementation of a subsystem, and is largely irrelevant to strategy, because how a robot plays is much more dependent on what it can do rather than how it does it, for example, whether the robot uses a scissor lift or a forklift style pulley system to lift the balls is not important because as they are both batched scoring systems they are subject to very similar performance and limitations.



We tried to estimate the performance of various subsystems to determine the effectiveness of the strategies. A batched lifter and scorer system is limited because it needs to be in a down position while collecting balls and a raised position while scoring, so its scoring rate is reduced by its travel time. A continuous feed lifter and scorer system, on the other hand is limited by needing to have a goal on hand and its requirement to handle balls in single file (this is a simplifying approximation that we assume will be proven wrong at some point.). We computed the average density of the balls based on the assumption that they would be uniformly scattered across the field area. That density allowed us to estimate the rate at which an intake of a given width would encounter balls. These calculations allowed us to estimate the scoring potentials and limiting factors of each potential design, so that we can make an informed decision about what type of robot we want to build.

Ben Trout

2014-09-24

Brainstorming, Calculating

Brainstorming	We established our intake last week so we went over our lifter/scorers and went over what path we want to pursue using pros and cons of all the ideas the team had.
Calculating	We started by doing a bunch of calculations to see if it is even possible to launch a ball to the correct height. Alex is in charge of the calculations but Filip and I helped him with measurements. See Alex's notebook for calculation

Brainstorming

As a team we went through all the pros and cons of our four lifter/scorers:

Batched:

Pros: possible, easy, reliable, simpler Cons: unreliable

Continuous Feed: Pros: faster than batched Cons: unreliable

Scissor lift with conveyor belts: Cons: complex mechanically, take up a lot of room, require a lot of power to run, slower than a shot, Gear system to reverse direction of belts: difficult to build

Pros: continuous feed, multiple balls traversing mechanism at once, possible with the parts that we have at hand, store balls along conveyor belt and score balls in end game.

repeating sling shot: Cons: requires large rates of fire, needs to be super reliable, needs to be able to handle a failed shot, wearing out the surgical tubing (loses elasticity over time)

Pros: Faster feed, lower transit times (to not get penalized for carrying more than 5 balls), reliable, easy to build, shoots straight up, more consistent than spring shot, faster reset time than spring shot

Spring shot: Back up plan if slingshot fails

Belt variant: Cons: very slow (but not as slow as scissor lift) balls could fall off easily, hard to build, unreliable

Pros: see pros of scissor lift

Guide tube with pulley system: hard to build a telescoping tube, manufacture the plastic tubing very precisely. and integrate pulley system.

Best Idea: Sling shot

We are going to split our group into two teams: One to prototype the intake system and one to prototype the sling shot. We are going to design them first and get a bill of materials.

We split of into two groups for the two prototypes: Intake: Mat, David, Alex Slingshot: Ben, Filip, Nick

Math

Me, Nick, and Filip helped Alex calculate whether or not we can actually launch the balls 120cm with the surgical tubing we have. See Alex's engineering notebook for all math calculations.

Filip Lewulis

2014-09-24

Research and Calculations

Intake calculations	Matthew and David looked over the ideal geometry for the intake device to the slingshot.
Launch calculations	Alex, Ben and I calculated the power output of the Tetrax DC motors, 10.98W and the mass of the balls, 28.9g and 11.68g to compute the theoretical maximum rate of fire.

We will

focus on rewriting this in a LaTeX file. We organized the team into the FTC7347 Github organization. For the launch calculations, Alex introduced us to LATEX format. Today I watched the PTC Robotalk Introduction for an introduction to CREO.

Nick Vosseteig
 2014-09-24
 Github and sick

Github	Reflections (how it went): Unfortunately I was home sick for most of the classtime this weeks and was unable to get much done because of this. However, I did manage to set up a github account and familiarize myself with the website. The other team-mates did this as well.	Nar-
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rative (please be detailed in your descriptions of challenges, solution efforts and achievements, and include photos and drawings):

I wasn't able to do much this week since I was sick for so much of the week, but our team managed to set up github accounts for our team and each individual team member. This will allow us to organize our engineering notebooks and we can work on the same things at the same time more easily.

David Rohrbaugh

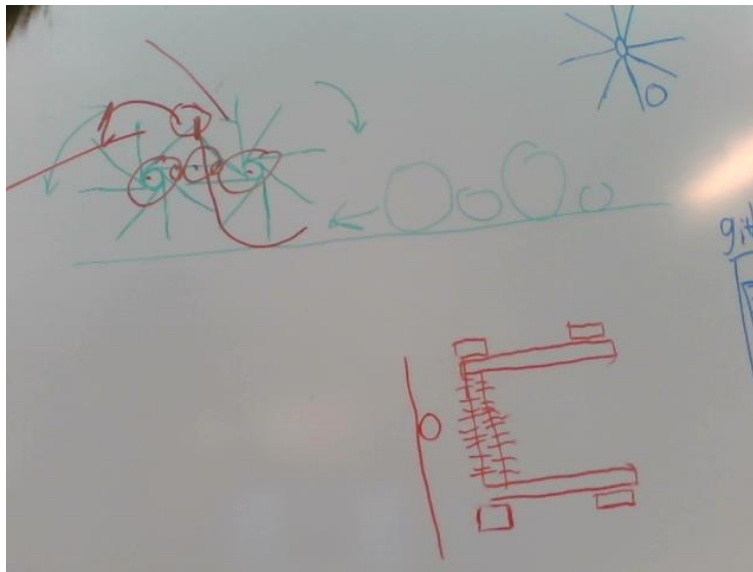
2014-09-26

The Intake Mechanism and Git

This week I worked on the intake mechanism, as well as setting up Git on my laptop. I started to calculate the required deflection of the blades of the intake mechanism requires.

The blades will have to deflect a lot, but I do not know how much yet. Finding a suitable material will prove a challenge.

These are two drawings of a proposed intake mechanism.



Alex Iverson

2014-09-29

Designing Mechanisms

Analyzed pros and cons of various mechanisms	Although fairly straight forward, this discussion was also hampered by miscommunications regarding Mechanisms and Subsystems
Began computing requirements for mechanism	This is much slower progress than it should be. Most team members' lack of prior math and physics training means that each calculation has to be accompanied with lessons and explanation

We have decided that the mechanisms we want to attempt to build first are a rotating brush intake and a slingshot based lifter. We have divided up into two teams. I am drifting between them, helping explain what we need to do to design them and figure out what parts we need to order before we go out and buy them. My brother is working on the intake; he needs very little guidance. The lifter team, however, has not yet completed a physics class; given how slowly the design and calculations are progressing right now, I will probably have to switch from showing them how to do the calculations to showing them by doing the calculations. I am confident that once we have designs and materials, the other team members will be much more productive.

Motor load current draw = 0.91A

Motor voltage = 12V

Motor power = $0.91\text{A} \cdot 12\text{V} = 10.92\text{W}$

Mass of large ball = 28.9g = 0.0289kg

Density of polycarbonate = $1.22 \frac{\text{g}}{\text{cm}^3}$

Thickness of plastic = 0.125in = 0.3175cm

Diameter of large ball = 2.8in = 7.112cm

$\Delta\text{height} = 120\text{cm} = 1.2\text{m}$

$$\Delta U = mg\Delta h = 0.34\text{J}$$

$$t = \frac{\Delta U}{P} = 0.031\text{s}$$

$$f = \frac{1}{t} = 32\text{Hz}$$

What we are doing now would ideally qualify as prototyping, however, it is being executed far too slowly and ponderously to be call it such. The scarcity of materials for our team means that we can't just put together a wood and cardboard mockup to sanity check the ideas. The rest of the team would much rather tinker, and I want to agree, but we do not have all the components required for our ideas on hand, and if we just start buying things without a reasonable idea of what we need then we are likely to run out of money before being able to finish our robot.

our team name has not been decided yet.

Filip Lewulis

2014-10-01

Designing

Designing	We considered the lifting mechanisms from looking at last year's FTC competition, but our calculations for intake appear to remain viable. Alex has written the LaTeX for the maximum rate of fire while introducing us to the syntax. I am following the PTC Robotalk tutorial for using CREO. Ben is researching the materials we can use in accordance with the rules for the robot's components. The launch mechanism is being designed by Matt, David, and Nick. And in accord, our team name is Children of the Matrix , which is nice, I guess.
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We're all working independently, but next week we plan to reconcile our efforts and begin actual construction of the robot.

Ben Trout

2014-10-03

L^AT_EX formatting for engineering notebook, Promoting FIRST

L ^A T _E X	We started our engineering notebook on google docs, but it didn't take us long to realize that it was very confusing and not organized at all. We switched to L ^A T _E X using Git as our source control system. TexWorks is the editor that we use.
Promting FIRST	We got six tasks as a group to promote our team to the community and get others to hear about our team. Another main purpose for these six tasks was for obtaining sponsors and others who would want to support our team.

L^AT_EX

Do to difficulties with google docs we, as a team, made the decision to switch to L^AT_EX. At first I was hesitant as it seemed really hard and inefficient. But after we all learned how to code it, push, and pull the engineering notebook I came to the conclusion that it will be more organized, easy to read, and better to format math.

Promoting FIRST

We have six tasks, one task per person on our team. The six tasks are as follows. Matt is in charge of an essay to get a 3D printer. Filip is in charge of designing on creo a piece we could print using the 3D printer. David is in charge of developing a simple code to move a servo motor to show other people or potential sponsors. Alex is in charge of making a brochure about our team and FIRST to obtain sponsors or to show other people interested in our team or program. Nick is in charge of designing our logo for our team. And finally I am in charge of making a team website to not only promote our team to the greater community, but also promote FIRST. I have a page with example engineering notebooks, a page describing our team, and a page describing our community outreach through out the year. There isn't a whole lot done yet with the website other than the fact that it is created. The website is a build in progress that will be updated throughout the year as we obtain information and do other things.

Here is a link to our website: <https://sites.google.com/a/libertycommon.org/children-of-the-matrix/>

Nick Vosseteig

2014-10-03

Set up, helping other teams, and finding materials.

Set up	One thing we did this week was set up Miktex and Github, and moved over the other engineering notebooks that we had written beforehand into the new system. We now have everything set up and engineering notebooks in the future will be easier to format/create.
helping other teams	Since there are two other, less experienced teams at our school, this week I also helped them set up the programs that they needed to test out some of the things they had built for their robot. Most were unfamiliar with RobotC, so I helped them to write basic programs.
finding materials	We decided to buy some surgical tubing this week so that we can start building a prototype of the launcher next week.

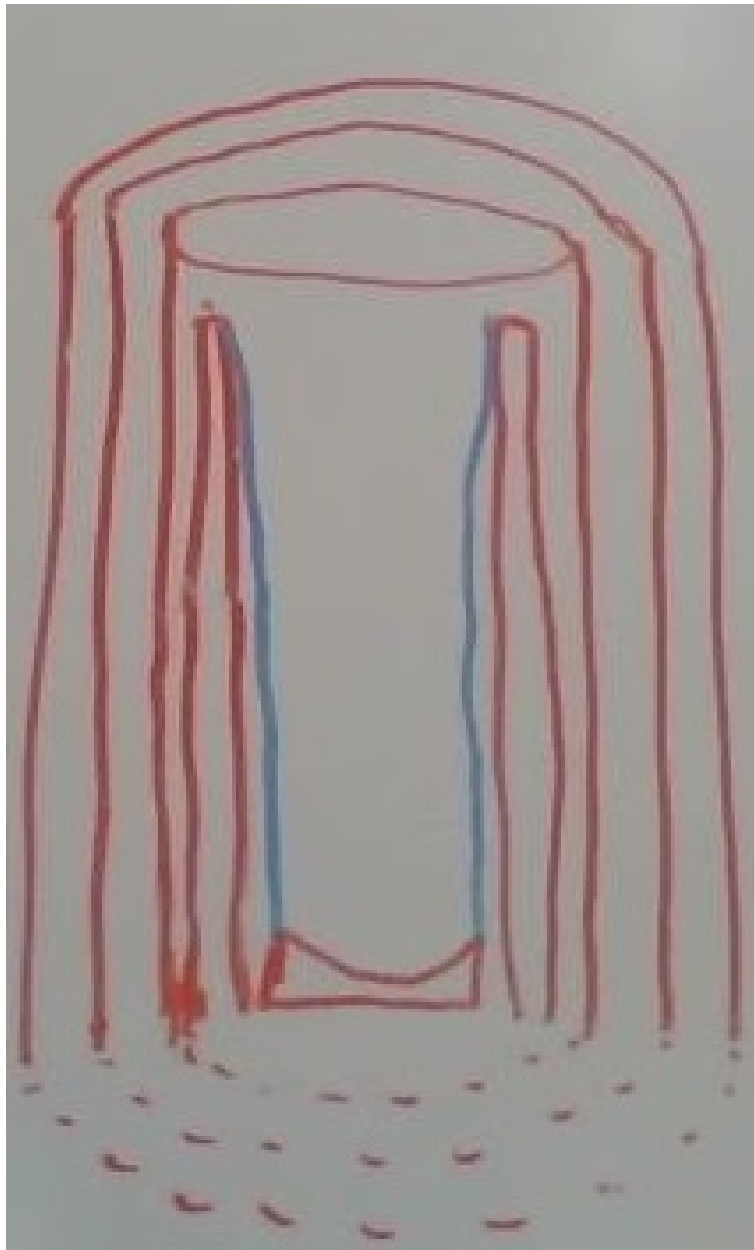
Miktex and Github

This week the main thing we worked on was setting up Miktex and Github so that we can format our engineering notebooks in a more consistent and better formatted.

Helping other teams

The other thing I did this week was help the other teams program their prototypes for certain parts. This was hard because none of them had any experience with programming previously. I managed to help them write some code that allows them to control the motors on their robot with the logitech controllers.

The last thing we did was come up with a basic design for the launcher and tube mechanism that we plan to build with the surgical tubing we are going to buy.



Alex Iverson

2014-10-06

Git, L^AT_EX, Engineering Notebook, and Calculations

Setting up Git	I walked the team through the process of creating github accounts, installing git, and configuring it. This was not very smooth, and I still have work to do making sure everyone is able to use these tools well. Ideally we would have done this in the preseason.
Setting up L ^A T _E X	I walked the team through installing MiKTeX. This went relatively smoothly, but there is still a ways to go before everyone is able to use L ^A T _E X and the editing environment well.
Converting the Engineering Notebook.	I created the basic file structure for the Engineering Notebook and began converting the entries into L ^A T _E X.
Calculations for the slingshot scorer	I ran calculations for the theoretical maximum rate of fire that could be achieved based on the motors' power output. The results suggest that the design is plausible, but it is sufficiently close that I will refrain from judgement until we have a demonstrable prototype.

The Git Bash and MiKTeX are now installed on our team's computers. We will be writing our Engineering Notebook in L^AT_EX because it is a better system to write technical documents in than the Google Doc we started with. Git's distributed source control allows us to collaborate more effectively and reduces conflicts from concurrent editing. It will also allow us to maintain source control even when we don't have internet access like at a tournament.

Here are the calculations for the slingshot:

Motor load current draw = 0.91A

Motor voltage = 12V

Motor power = 0.91A · 12V = 10.92W

Mass of large ball = 28.9g = 0.0289kg

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Thickness of plastic = 0.125in = 0.3175cm

Diameter of large ball = 2.8in = 7.112cm

Δheight = 120cm = 1.2m

$$\Delta U = mg\Delta h = 0.34\text{J}$$

$$t = \frac{\Delta U}{P} = 0.031\text{s}$$

$$f = \frac{1}{t} = 32\text{Hz}$$

$$K = \frac{1}{2}mv^2 = 0.34\text{J}$$

$$v = \sqrt{\frac{2K}{m}} = 4.9\frac{\text{m}}{\text{s}}$$

$$m_{\text{plastic}} = (1.5 \cdot 7.112\text{cm})^2 \cdot 0.3175\text{cm} \cdot 1.22\frac{\text{g}}{\text{cm}^3} = 44\text{g}$$

$$K_{\text{plastic}} = \frac{1}{2}m_{\text{plastic}}v^2 = 0.529\text{J}$$

$$K_{\text{total}} = 0.34\text{J} + 0.529\text{J} = 0.869\text{J}$$

$$t = \frac{K_{\text{total}}}{P} = 0.079\text{s}$$

$$f = \frac{1}{t} = 12.5\text{Hz}$$

David Rohrbaugh

2014-10-10

Tasks Related to the 3D Printer and Joystick Control

<p>This week I worked on getting a servo motor working with a joystick. Even though I had the correct code, RobotC was not set up the right way, so it did not work. Nick's computer was set up correctly, so when the code ran on his computer it worked.</p>	<p>I was finished with the task of getting the joystick and servo working by the end of class Thursday. I missed class on Friday, but my teammates continued their work on their tasks. Nick has a lot more code which can be used as a template for doing basic tasks.</p>
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Nick Vosseteig

2014-10-10

brainstorming, helping other teams, and testing.

Brainstorming	We brainstormed methods to repeatedly fire our slingshot and came up with two possible solutions of a winch with a clutch, and a wheel attached to the ball-holder.
helping other teams	I continued helping the other teams since they are less experienced with programming. David set up the hardware to test simple programs by using the joystick. This week I also set up a few sample programs that people can reference or test out with the hardware to see how the code works.
testing	We tested out the surgical tubing by using a makeshift launcher with 2 chairs and a cup attached to the tube in order to test launching the balls. We determined that it does not need to be pulled down very far to launch the balls as high as we need to, but it takes a substantial amount of force to pull down. If we use less tension, it needs to be pulled down further, but takes less force to do it, but having a much shorter, higher tension launcher could increase reliability and make the mechanism easier to work with.

Helping other teams

Helping the other teams with programming is something that I've been working on alot and this week I came up with some short sample code to show them:

```
#include "JoystickDriver.c"

task main()
{
    while(true)
    {
        getJoystickSettings(joystick);
```

```
    if(joy1Btn(1)){  
        servo[servo1] = 255;  
    }  
    if(joy1Btn(2)){  
        servo[servo1] = 0;  
    }  
}  
}
```

It's very simple code, but it helps them to understand how to set up their code and allows them to understand this simple code on how to use a servo motor with the joystick controller.

Testing

We tested out the surgical tubing, but the problem is whether we should use a lot of tension or a little tension. There are pros and cons to both sides: Having less tension means that the tubing needs to be pulled further down, but it would be less hard on the motor doing it, having more tension puts more pressure on the motor, but allows for a more reliable, and more compact slingshot.

Filip Lewulis
CREO Modeling

Modeling	Our team worked in Parametric to design the ball container. Will helped us greatly.
Robotalk	PTC Webinar Notes:

Our productivity is still slowed by lack of materials.

David Rohrbaugh

2014-10-16

Code for Controlling Robot Remotely

This week I worked on setting up a basic robot, specifically, incorporating the gamepad and electronics. We now have basic code for a servo and a DC motor.	We have the basic framework in place, but it will have to be fine-tuned.
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David Rohrbaugh

2014-10-17

Code for Moving Servo with Joystick

Today, I worked with the rookie team on making a servo work with the joystick. We were not able to get it to work, but this year being my first year coding in RobotC and uncertainty over whether the computer was set up right didn't help.	I and the person I was working with both learned a lot more about using RobotC with joysticks and servos despite failing to move the servo with the joystick.
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Nick Vosseteig

2014-10-17

helping other teams, testing, logo design.

Helping other teams	This week I helped other teams by creating some more sample code. I also built a simple model showing how wiring works. It has a servo controller and a dc controller so that I can show the sample programs with it.
testing	We continued testing the surgical tubing as well as began building a prototype for the intake device.
logo design	I made a logo for our team this week.

Helping other teams

This week I created another sample program that uses the logitech controller to control the motors.

```
#include "JoystickDriver.c"

task main()
{
    while(true)
    {
        //each stick controls a motor
        getJoystickSettings(joystick);

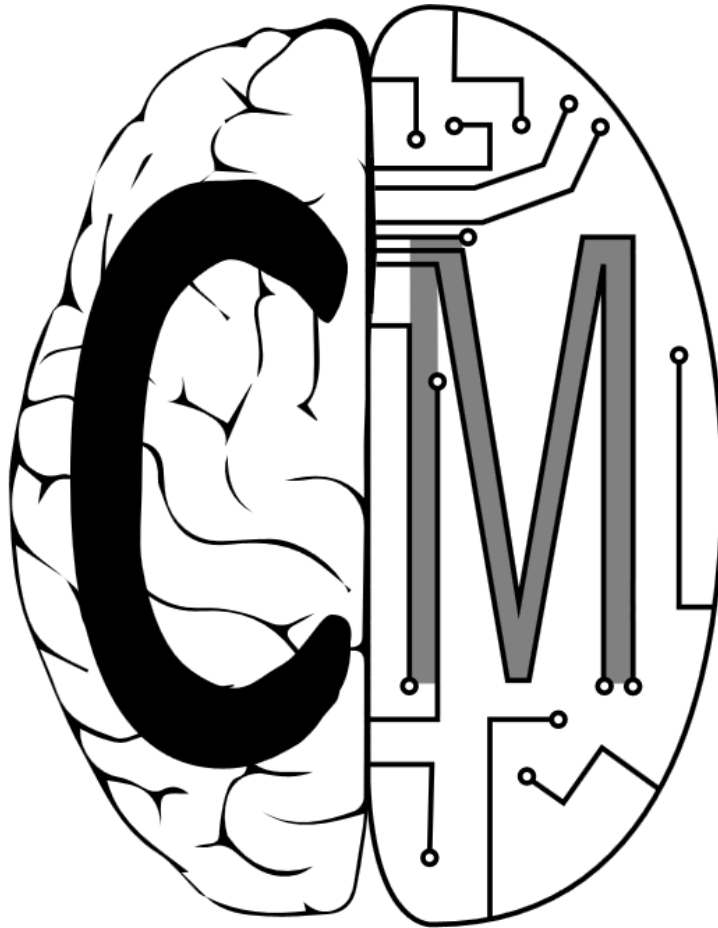
        if(joystick.joy1_y1 < 20 && joystick.joy1_y1>-20)
        {
            motor[dc1] = 0;
        }
        else
        {
            motor[dc1] = joystick.joy1_y1;
        }
    }
}
```

The code shows people how to move the motors using the joystick, demonstrates using a deadzone for the joystick, and shows them how to use dc motors.

Logo Design

I created a logo for our team - Children of the Matrix. The logo has a brain, with one half being organic and the other half looking like part of a computer. Children of the Matrix means people who can connect to the internet with thier minds, so I found the brain with two sections fitting. I also added in the two

prominent letters from our name into the brain: C on the organic side of the brain and M on the technological side. Here is a picture of the logo:



David Rohrbaugh

2014-10-22

Code for Moving Servo with Joystick

This week I worked on building the field with Ben and Filip. We cut out most the plywood pieces at a friend's shop, and finished cutting out the pieces at our on-site shop.	The only thing that remains to be done is screw all the pieces together.
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David Rohrbaugh

2014-10-31

Prototyping the Intake Mechanism and Joystick Control

This week I, with several teammates, worked on prototyping the intake mechanism.

Our current intake mechanism is a folded cardboard panel. It will most likely be replaced by a more suitable material. This material must be able to deflect enough, however, to collect balls when the robot is up against a wall.

This is a diagram of our current prototype for the intake mechanism. A Tetrix channel is attached to a DC motor so it rotates as shown. The cardboard, which will probably be replaced by a more suitable material, makes contact with both sizes of balls, pushing into our yet-to-be-constructed launching mechanism.

