










5839B's Notebook

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Post Season Build Analysis

For the building of our previous robot even though it unfortunately did not make worlds there were a lot of aspects executed properly and poorly to be identified. This is important as it allows the team to know what works and to keep doing as well as what to change in order to improve for the next season.

Drive Train The Drive Train is the base of any robot. The previous seasons drive train used 6 11w motors with the blue cartidge and a 48:60 gear ratio giving an RPM of 480. This spun 3 omni wheels with the middle one on each side being locked.

Pros

- Speed
- Pushing power
- Strong Wedge

Cons

- Turning
- Reliability
- Over Heating
- Field Traversal

Intake The intake was powered by 1 5.5w motor spinning a series of 2in 45A flexwheels to interact with the game objects. The intake was also allowed to float so that it could raise over the goal to score the triball.

Pros

- Holding ability
- Scoring
- Reliability
- Effectiveness

Cons

- Chain Broke once

Wings These were pneumatically activated flaps that would extend 9in on either side of the robot. These allowed for a large amount of game objects to be pushed into the goal at one time.

Pros

- Never failed
- Reached corners
- Simple Design

Cons

- Bent after multiple matches

Flywheel Arm this was a 4in Flexwheel with a ratchet spinning at 3600 RPM off of a blue motor. Game obejcts were placed and launched off of the flywheel. It could also be raised by a 5.5w motor assisted by rubber bands to shoot over other robots.

Pros

- Consistent firing
- Fast firing
- Height
- Ratchet persrved motor health

Cons

- Unable to use the arm for climbing
- Flywheel got jammed on a standoff in 2 matches

Odometry Modules These are 3 modules 2 vertical and 1 horizontal that are used to track the robots position. They are jointed to always be in contact with the ground, and have a 3.25 in omni wheel spin an encoder to track movements.



Pros

- Simple Design

Cons

- Bent over time
- Large
- Unreliable ground contact

What to do now?

- With the biggest problem being the drive a variety of drives should be modeled and tested in order to have a better idea of what works for the next season
- Work to create new odometry module designs that are stronger and more compact
- Take inventory of the parts available to our team so that when designing we know what parts we can use and how many of them are available
- Put together an order list of parts that the team wants to assess the needed funds
- See what funding is available to the team and what amount should be allocated to new parts
- Look into making a functional PTO (power take off) as they can allow for more powerful drives while still having all the desired mechanisms to manipulate game objects
- Look for or model our own paddles for the controller that suite the needs of our driver



Before any models for possible drive trains or new odometry sensors can be made a decision on what software to use is necessary. In the previous season we adopted Autodesk inventor. There were a variety of reasons for this the primary one being familiarity. At Eastern Technical Highschool there is an Engineering Magnet program which teaches Autodesk inventor. This not only means over half the team who is in this program know the software, but also there is 3 teachers who can assist us with any issues. Also with Inventor being used by the school the county provides a VDI or Virtual Desktop Interface where you can log in remotely to a desktop with Inventor. This allows the team who does not all have access to a high quality laptop to access the model on the school issued chromebooks. Due to these reasons we find it impractical to switch design softwares. Not only would we have to remake some of our premade assemblies such as for flex wheels, but we would have to spend time learning new software which outweighs any of the other softwares advantages.



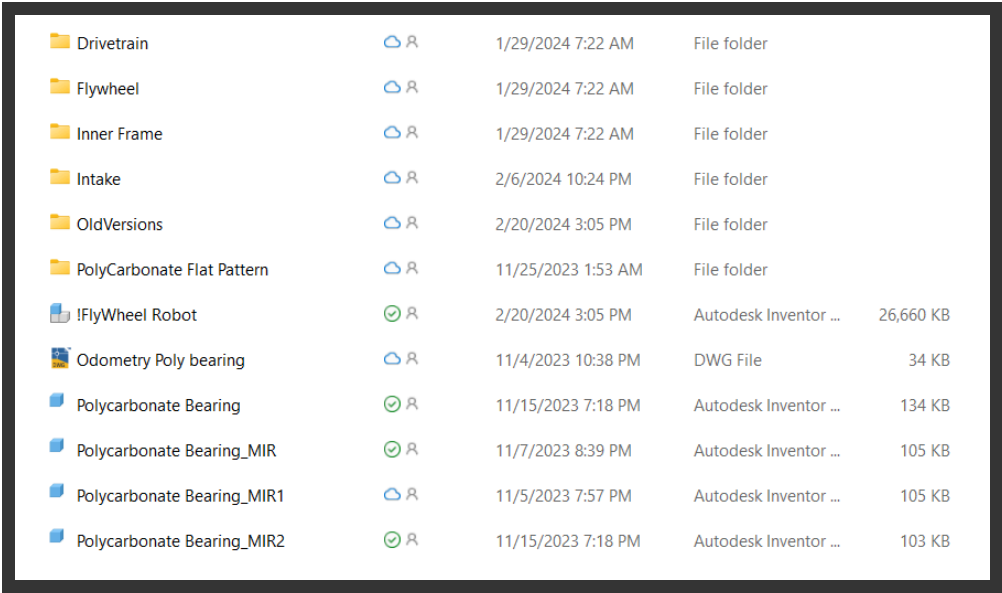


To effectivley use any software wether for coding or modeling file organization is key. To share these files the team makes use of Microsoft Onedrive since it works best with windows device which the majority of the team has.

For the Inventor the main robot assembly is made from a variety of sub assemblies. These sub assemblies are each for a key system such as the drive train or intake. There can exist further sub aseemblies within these as well such as that for the odometry sensors within the assembly they are attachetd to. To organize the many file for this a variety of naming conventions are used based off of the guide lines from Perdu Sig Robotics.

- Robots are marked with a folder labeled “! Robot Name”
- Within in that folder is the main assembly of the same name
- Assemblies or cut parts used throughout the model are stored in this high level folder
- There are also folders with each of the sub-assemblies labeled “Assembly Name”
- Within the sub-assembly folders are all the special cut parts and sub-assemblies of that Assembly.
- All other parts are stored in a default parts folder with every vex part organized by type

This system comes with a variety of advantages for the team. Individul axels or mechanisms be edited without opening the whole robot which allows team members to interact with the models without a powerful computer. It also allows for big changes to be made easier as the major sub-assemblies can be removed or changed without having to edit a bunch of individul parts. This also helps during the build process as we can divide the many sub-assemblies between any teammembers without other work to do. This has proven in the past to allow us to build full redesigns in just a week and half such as what we did after dulaney last year.



Drivetrain	Cloud icon	1/29/2024 7:22 AM	File folder	
Flywheel	Cloud icon	1/29/2024 7:22 AM	File folder	
Inner Frame	Cloud icon	1/29/2024 7:22 AM	File folder	
Intake	Cloud icon	2/6/2024 10:24 PM	File folder	
OldVersions	Cloud icon	2/20/2024 3:05 PM	File folder	
PolyCarbonate Flat Pattern	Cloud icon	11/25/2023 1:53 AM	File folder	
!FlyWheel Robot	Checkmark icon	2/20/2024 3:05 PM	Autodesk Inventor ...	26,660 KB
Odometry Poly bearing	Cloud icon	11/4/2023 10:38 PM	DWG File	34 KB
Polycarbonate Bearing	Checkmark icon	11/15/2023 7:18 PM	Autodesk Inventor ...	134 KB
Polycarbonate Bearing_MIR	Checkmark icon	11/7/2023 8:39 PM	Autodesk Inventor ...	105 KB
Polycarbonate Bearing_MIR1	Cloud icon	11/5/2023 7:57 PM	Autodesk Inventor ...	105 KB
Polycarbonate Bearing_MIR2	Checkmark icon	11/15/2023 7:18 PM	Autodesk Inventor ...	103 KB

Inventor Files from the Over Under Season



Before any designing can take place it is key to know the constraints one is placed under. For vex a key way of doing this other then reading the rules is too see what parts are available to your team. You may have the best idea for a design but without hte parts to build that idea is jsut waisted time.In order to see what parts we had an excel spread sheet was created with all Vex Parts that were in our Inventor parts library as well as newer ones found the Vex website. Additionally Tools and other accesories from the Robosource website were included that we deemed may prove useful.

1819 Vex Parts inventory											
Hardware			Structure			Motion			Electronics		
Part	Amount	Type	Part	Amount	Type	Part	Amount	Type	Part	Amount	Type
0.25" torx screw		2-wide aluminum c-channel	LS Bearing Flat		LS Bearing Flat	Beam		Hex Drivers			
0.25" hex screw		3-wide aluminum c-channel	Pillow Bearing		Pillow Bearing	Controller		Wrenches			
0.375" torx screw		3-wide aluminum c-channel	LS Shaft Collars		LS Shaft Collars	Battery		T-35 Drivers			
0.375" hex screw		2-wide steel c-channel	LS Shafts		LS Shafts	11v Motor		T-2 Drivers			
0.5" torx screw		3-wide steel c-channel	4" Traction Wheels		4" Traction Wheels	Blue cartridge		Hex Ball Drivers			
0.5" hex screw		3-wide steel c-channel	3.25" Traction Wheels		3.25" Traction Wheels	Red cartridge		T-35 Ball Drivers			
0.625" torx screw		Lexan	2.75" Traction Wheels		2.75" Traction Wheels	Green cartridge		T-35 Alan Keys			
0.625" hex screw		Acetal	0.4" Left Mecanum Wheels		0.4" Left Mecanum Wheels	1.5" Vex Motor		Hex Allen Keys			
0.75" torx screw		Aluminum Plates	4" Right Mecanum Wheels		4" Right Mecanum Wheels	Radio Receiver		Bit Magnetizer			
0.75" hex screw		Steel Plates	2" Left Mecanum Wheels		2" Left Mecanum Wheels	Optical Shaft Encoder		T-35 Power Bit			
0.875" torx screw		30 degree flat gussets	2" Right Mecanum Wheels		2" Right Mecanum Wheels	Vex Cables		Hex Power Bit			
0.875" hex screw		45 degree flat gussets	4" Omni Wheels		4" Omni Wheels	3 wire extenders		Needle Nose Pliers			
1" torx screw		60 degree flat gussets	3.25" Omni Wheels		3.25" Omni Wheels	3 wire extenders		Bolt Cutters			
1" hex screw		80 degree flat gussets	2.75" Omni Wheels		2.75" Omni Wheels	Solenoid 3 wire cables		Flash Cutters			
1.25" torx screw		30 degree bent gussets	2" Omni Wheels		2" Omni Wheels	Solenoids		Hammers			
1.25" hex screw		45 degree bent gussets	6T sprockets		6T sprockets	Battery Cables		Safety Glasses			
1.5" torx screw		60 degree bent gussets	16T sprockets		16T sprockets	Inertial Sensor		Drill			
1.5" hex screw		80 degree bent gussets	24T sprockets		24T sprockets	Vision Sensor		Air Compressors			
1.75" torx screw		Bevel Gearbox	32T sprockets		32T sprockets	Bumper Switch		Tool bags			
1.75" hex screw		Rack Gearbox	40T sprockets		40T sprockets	Limit Switch		Tool Boxes			
2" torx screw		Worm Gearbox	HS Chain		HS Chain	Battery Chargers		Robot Boxes			
2" hex screw			8T HS Gear		8T HS Gear	Micro USB Cables		Portable Battery Storage			
2.25" torx screw			16T HS Gear		16T HS Gear	Potentiometer		Cable Tester			
2.25" hex screw			48T HS Gear		48T HS Gear	AI Vision Sensor		Portable Vise			
2.5" torx screw			60T HS Gear		60T HS Gear	GPS sensor		3 Wire Crimper			
2.5" hex screw			72T HS Gear		72T HS Gear	Spiral Wire Wrap (Large)					
0.5" Shoulder Screws			84T HS Gear		84T HS Gear	3 Wire Cable Stock					
Lock Nut			HS Shaft		HS Shaft	3 Wire Cable Connectors					
Thin Lock Nuts			HS Bearing Flat		HS Bearing Flat						
Kept Nuts			HS Shaft Collar		HS Shaft Collar						
0.25" Standoff			HS Invert		HS Invert						
0.5" Standoff			1.8" Versa Hex Adapters		1.8" Versa Hex Adapters						
1" Standoff			1.4" Versa Hex Adapters		1.4" Versa Hex Adapters						
1.5" Standoff			Universal Adapters		Universal Adapters						

Top half of the Inventory Spread Sheet

2" Standoff			30A 1.625" Flexwheel	0
3" Standoff			30A 2" Flexwheel	
4" Standoff			30A 3" Flexwheel	
6" Standoff			30A 4" Flexwheel	0
Zip Ties			45A 1.625" Flexwheel	0
Rubber Bands			45A 2" Flexwheel	
.5" Hex Set Screw			45A 3" Flexwheel	0
1" Hex Set Screw			45A 4" Flexwheel	
1.25" Hex Set Screw			60A 1.625" Flexwheel	0
			60A 2" Flexwheel	0
			60A 3" Flexwheel	0
			60A 4" Flexwheel	0
			Flywheel Wiegth Plate	0
			Universal Joints	0
			Intake Rollers	
			Shaft Couplers	
			High strenght Ball Bearing	20
			High strenght Ball Bearing Frame	20
			High strenght Ball Bearing Square Insert	
			High strenght Ball Bearing Round Insert	
			LS lock bar	
			Double Acting Piston	
			Reservoirs	
			Pneumatic Tubing	
			24" HS Axels	0
			Hinges	
			Bevel Gears	
			Worm Gears	
			Inner Slide Trucks	
			Outer Slide Trucks	
			Pulley	

Bottom half of the Inventory Spread Sheet

The Spreadsheet will take a while to fill out, but for now parts with known quantities such as zero have been filled out. Those were marked with yellow to indicate more were needed. These were then taken



After a week of work we were able to complete all rows of the spread sheet and figure out what parts the team was in need of. A variety of methods were used to measure the various parts. Large parts like Wheels and Motors were counted but other parts required a different aporach. String wires, and tubing were measured in feet, and metal strcuture by its weight. For parts like screws and nuts a single unit was weighed as well as the container and the total amount we had. The weight of the container was then subtracted from the total and then divided by the unit to find the total quantity.



Note

We found our time managment to be extremely poor during this endeavor which greatly increased its length. To adress this we may work to change how the team meets to allow for not only more time, but better uses of that time.



New Drive Models

There exists a variety of drive models both practicle and impracticle that can be made with the VRC legal parts. It is important to judge where each one can shine to see which is the most practical when the next game releases. A decision can not be made yet for which drive is best, but the strenghts and weakness of each one can be assesed as well as models for the more practical ones generated. These models can give us a head start on the next seasons bot if they prove adequate for the next game as well as allow the team to test various ideas.

Tank Drive

A large variety of what can be considered a tank drive or differential drives exist within vex. These work by having two sides where each sides wheels all spin together. This allows for linear motion(Both sides spin the same direction), turning (Both sides spin opposite), and arcing (One side spins slower then the other in the same direction). These drives are often the simplist and provide a wide range of motion while remaining able to push back against other robots. These drives can also be achieved in a variety of ways with varying numbers and sizes of wheels that augment their performance.

4in wheels provide greater speed as per each rotation the robot moves farther, however they give the robot less torque. Additonally since less of them can fit onto a dirve with the 18*18*18 size limit there is also less points of contact. Additionally with the older 4in wheels the team currently own the traction versions are .125in smaller then the omni versions

3.25in wheels provide slower speeds, but are able to give the robot more pushing power as they have more torque and points of contact. These wheels are also easier to work with as the traction and omni versions are the same size unlike with the older 4in wheels

Omni wheels have rollers that allow the wheel to move side to side as well as forward and back. This makes them great for turning, but poor for traction.

Traction wheels wheels are all rubber and provide exceptional ground adherence for any robot, however they greatly limit turning making them impractical unless used as the middle wheel where there effects on truning are midigated.

From our teams expirience a 3.25in drive with 2 traction wheels in the middle and 2 omni wheels on either end appears to be the optimal way to execute this drive. Our previous drive with 3 4in omniwheels failed to push back agaisnt other robots that were using 3.25 in tank drives with the same amount of motors. These robots also were just as fast and maneuverable as ours showing little trade off for this design.

Pros

- Simplicity
- Versatility
- Easier to Control

Cons

- Limited Mobility
- Wheel incompatibilities

-> Tank Drives



H/X Drives

These use either 4 or 5 omni wheels to achieve a robot that has the same range of motion as a Tank Drive, but with the addition of diagonal and horizontal movements. They either use in the case of an X drive 4 individually powered omni wheels in each corner at 90 degrees from one another or 4 individually powered omni wheels in a traditional tank drive setup with one horizontal omni wheel for the H drive. These drives can however, prove difficult to control and in the case of the H drive impractical as the horizontal wheel rarely makes contact. They are also very easy to push around since all the wheels are omni. X drives can prove highly practical given the right game and design but in games such as over under the middle bar limits their use.

Pros

- Maneuverability
- Complex Autonomous
- Strafing

Cons

- Mechanical Complexity
- Motor Usage
- Practicality
- Low Traction/Easy to push

-> X/H Drives

Mecanum Drives

Mecanum drives are likely the most special as they use specialized mecanum wheels. These like omni wheels have a roller attached, but at an angle to provide uniquely augmented movement. When set up correctly 4 individually powered mecanum wheels can provide the same movement as a X drive. However, since to go in any direction it directly turns the mecanum wheels they are harder to push as the motors resist the pushing directly. This along with other issues can also lead to faster overheating with mecanum drives. The VEX EDR 4in mecanum wheels are very bulky putting more strain on the motor additionally, the VEX mecanum wheels unlike most designs have limited contact with the ground due to the irregular design of their rollers. It is also important to note it is easier to gear and build a frame for a mecanum drive over an X drive as it does not require the 45 degree angles to achieve its unique motion. Though also possible with an X drive an additional powered omni wheel could be put into the middle to provide more drive power. Since this wheel isn't needed at all times if a successful PTO can be developed it could allow for a very versatile robot and drive.

Pros

- Maneuverability
- Complex Autonomous
- Strafing

Cons

- Mechanical Complexity
- Motor Usage
- Practicality
- Requires balanced weight

-> Mecanum Drives

Swerve Drives

Previously considered impractical for VEX swerve drives involve either 3 or 4 independently steered and powered wheels. These focus around modules that can both rotate the orientation of and spin the wheels. This allows for the robot to turn rapidly as well as turn while moving. The wheels can be positioned



in the manner of a traditional tank drive for linear movement and then turned to go the desired direction. However until the addition of the 5.5w motors these would either use 6 or all 8 of the robots available motors. The 5.5w motors now allow for this drive to be possibly practical as a 3 wheel swerve drive could be made from 3 11w motors and 3 5.5w motors allowing for 38.5w of motors to be allocated to the robots mechanisms and manipulators. The advantages of swerve drives can be seen from other competitions like frc where they are often used to great success to create highly maneuverable bots. The use of one within vex would be highly dependent on the game as one that with limited room to move such as over under takes away many of a swerve drives advantages. It is worth creating a model for a swerve drive module in case the next game is one that prioritizes movement. It would also provide practice using more complex gearing which the team has yet to experiment with.

Pros	Cons
<ul style="list-style-type: none">• Maneuverability• Complex Autonomous	<ul style="list-style-type: none">• Mechanical Complexity• Motor Usage• Practicality

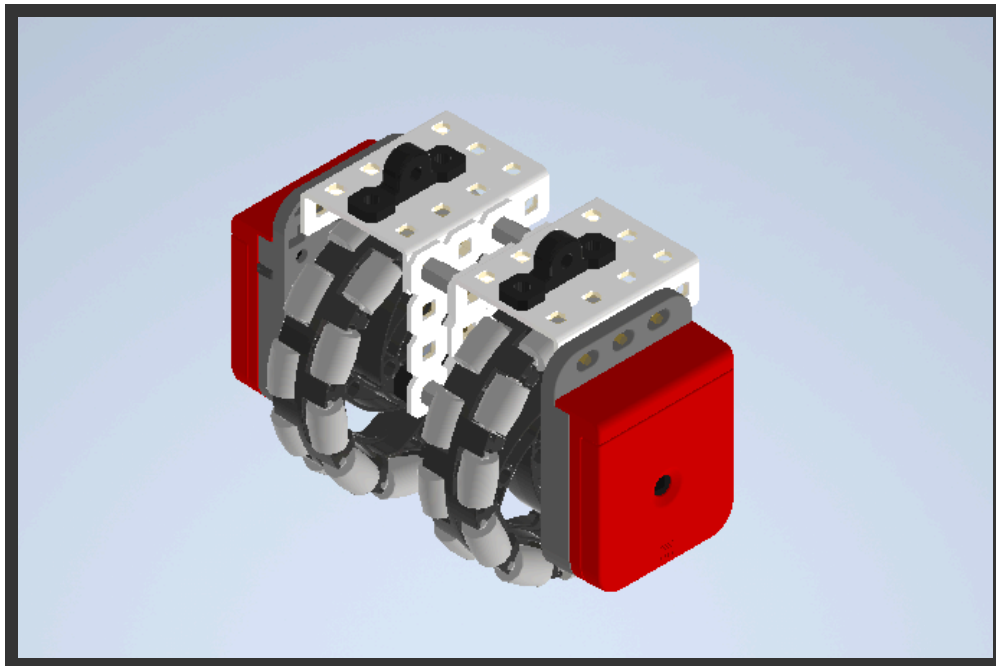
-> Swerve Drives



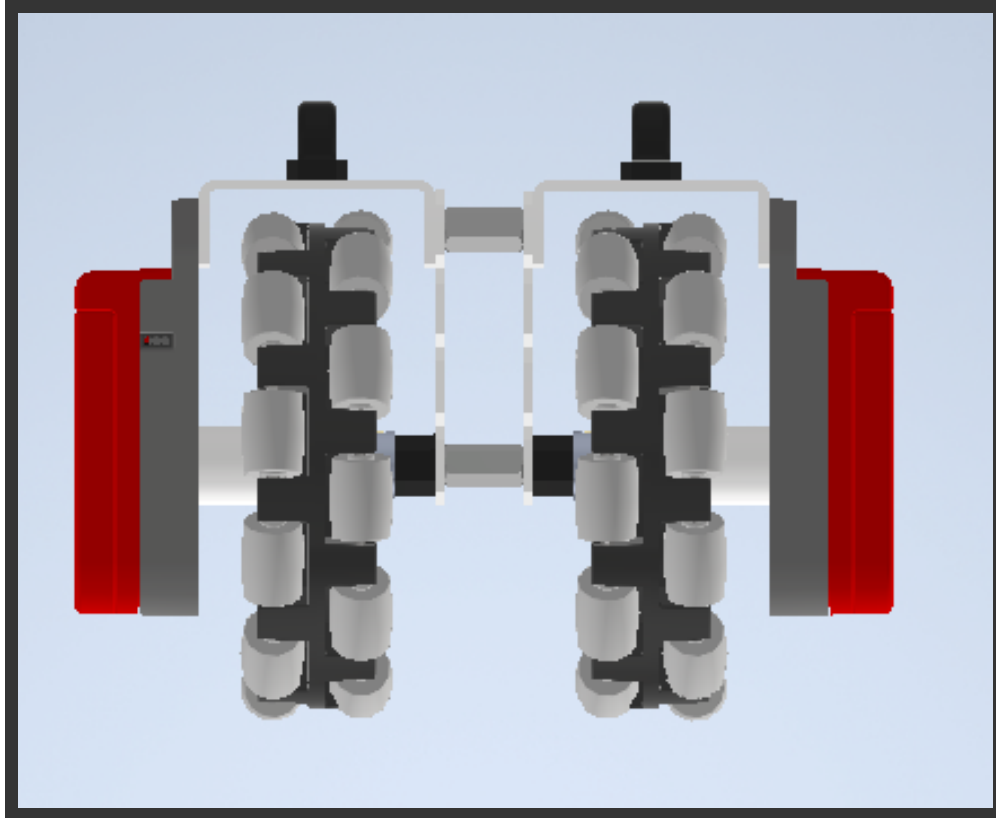
Odometry is a position tracking algorithm used by the coder to implement complex autons. It relies on three sensors 2 vertical and 1 horizontal. The failures of the previous design were compactness and resiliance and the new designs makes a few imprpovments to this area. It is important to complete this first as any prototype drives made must be designed to fit the sensors. This along with a basic mecnum drive which can act as a tank drive when need be will allow the coder to begin making some basic frameworks for next year.

New Design:

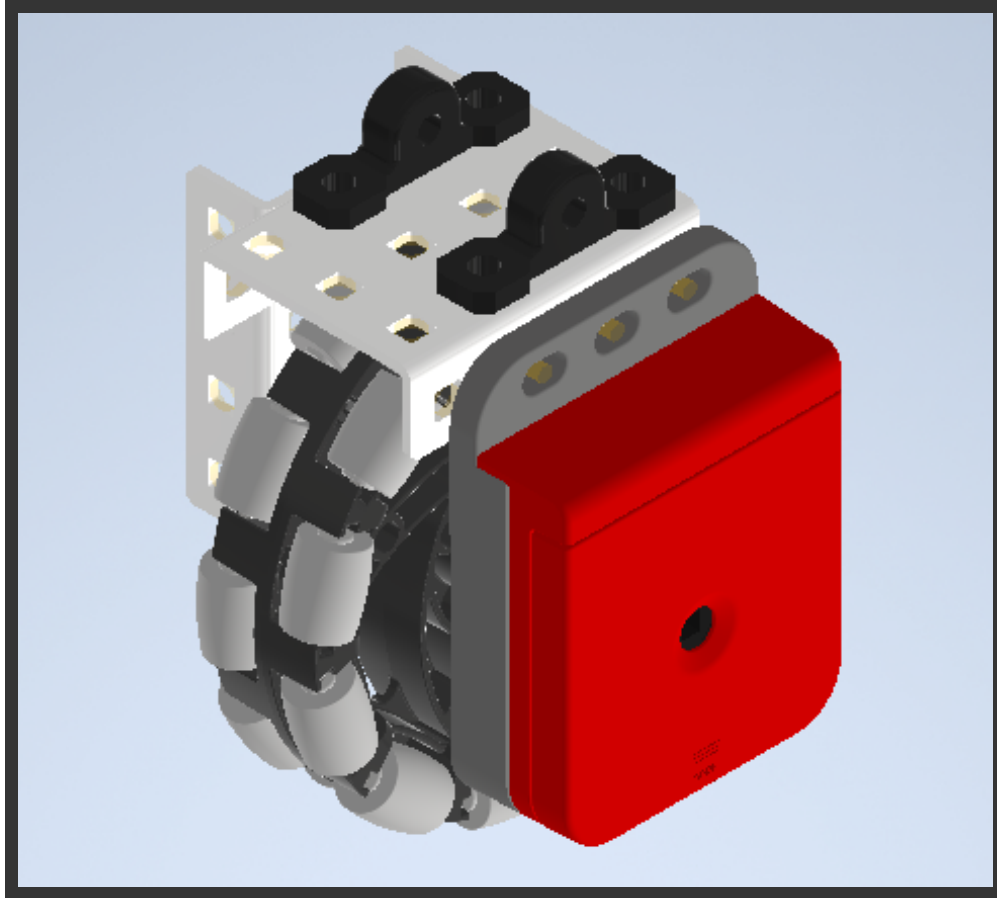
- Verical Wheels save space by being in the same module
- No plate is used without being reinforced
- Pillow bearings used to simplfy mounting
- Newer 3.25in wheels used for better traction



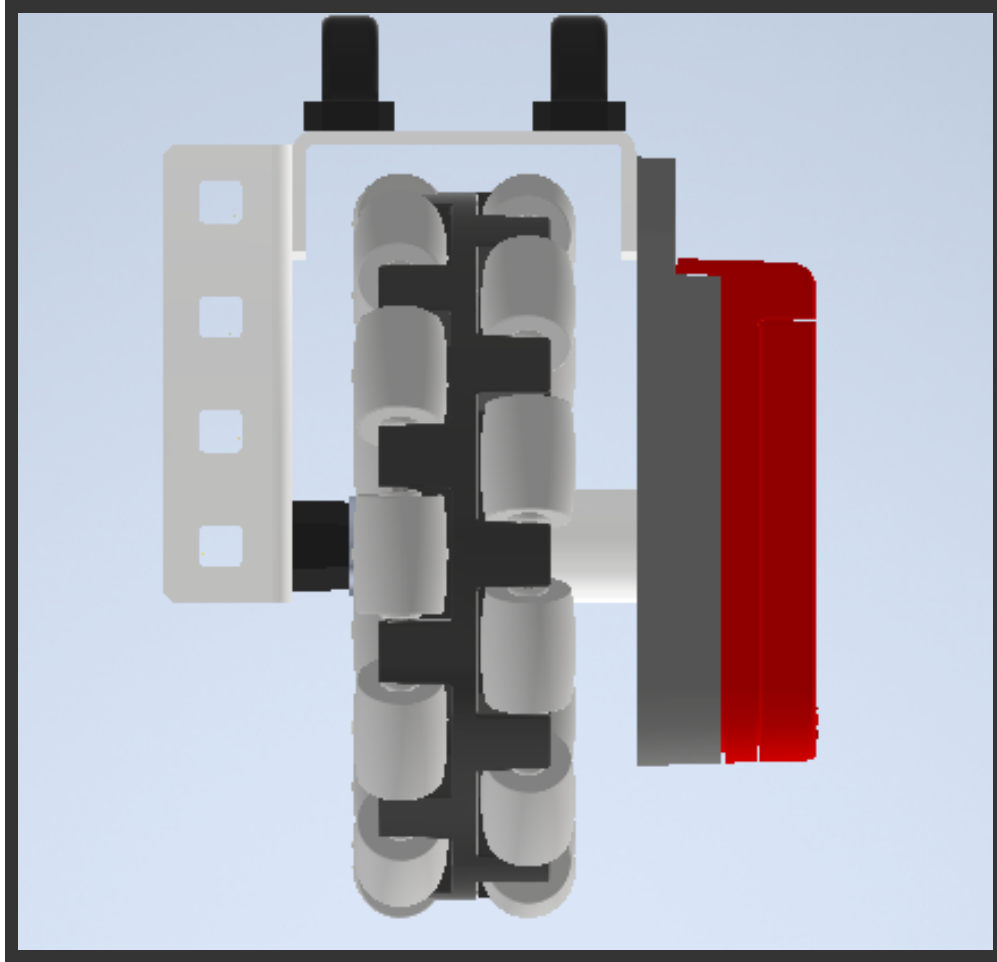
Isometric View of the New Vertical Odometry Sensor



Front View of the New Vertical Odometry Sensor



Isometric View of the New Horizontal Odometry Sensor



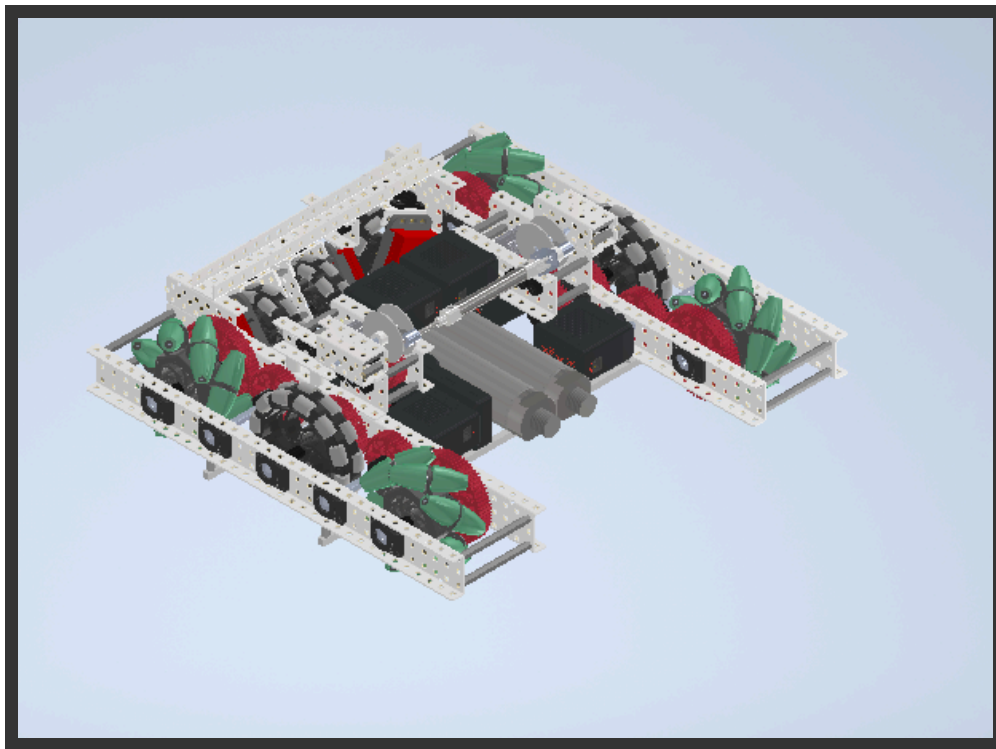
Front View of the New Horizontal Odometry Sensor



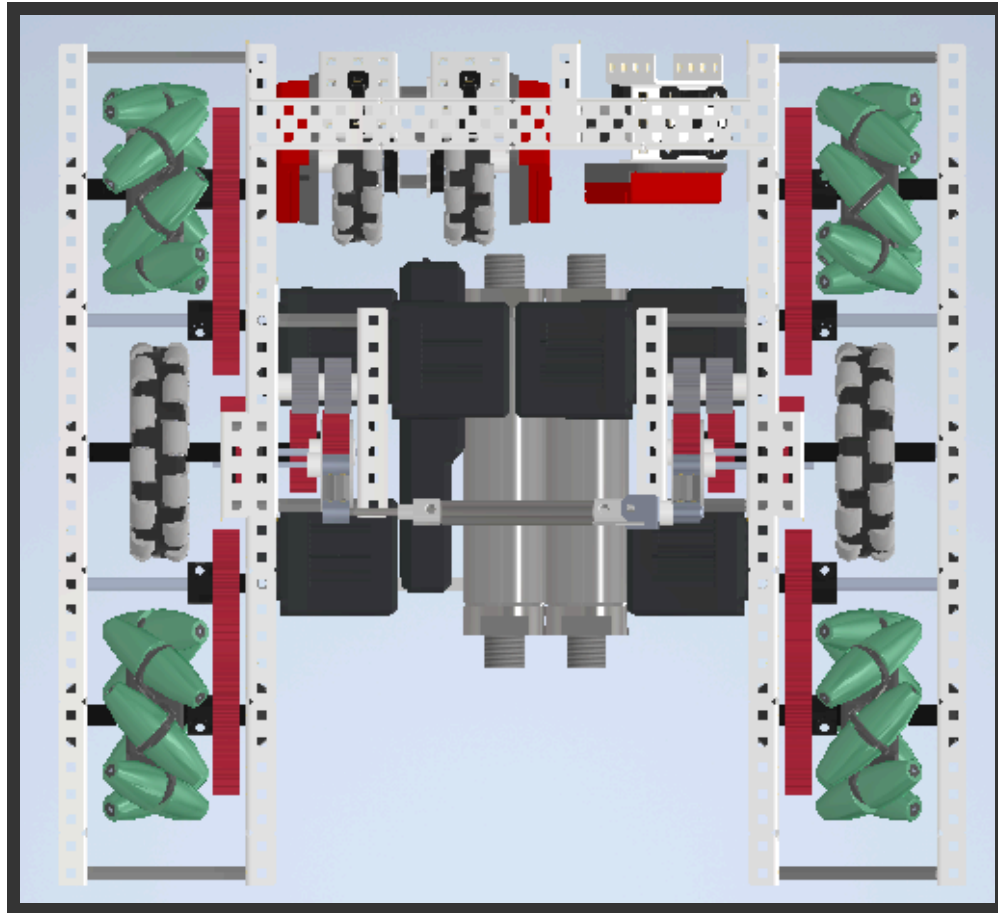
With inventory taken we can now begin to make some designs. To experiment with more complex Drives a Mecanum drive and a Swerve Drive module were completed. These should provide good practice for designing before the next season as well possibly giving us a head start if we choose to use these drives.

The first model made was that of a Mecanum Drive:

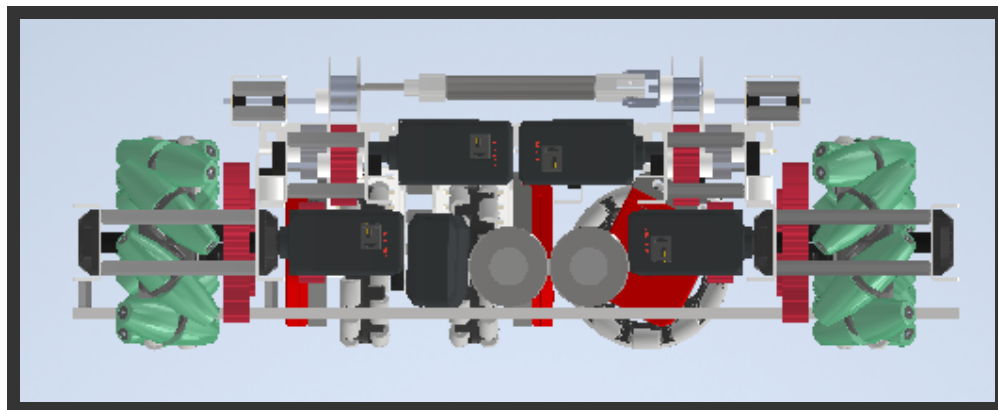
- 4 Mecanum wheels geared to 300 RPM with a 72:48 ratio driven by an 11w motor with the 600rpm cartridge.
- 24in HS axels with holes drilled in them as the main frame to ensure it was stronger then our previous drive trains.
- Center Omni Wheel for additional power
- PTO to allow for the center omni wheel to power other system while not in use
- Battery and Air Tanks kept low to ensure a proper center of gravity
- New Odometry Sensor fitted in the rear



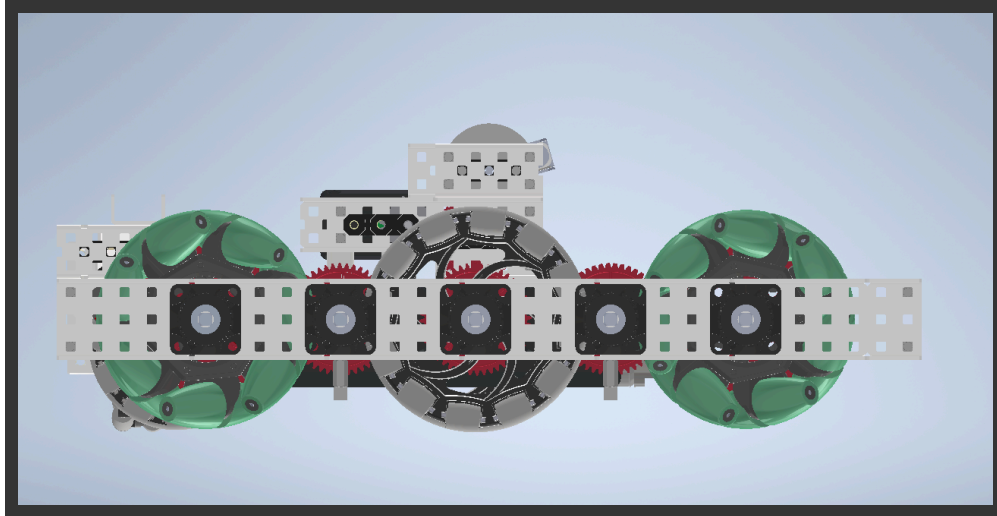
Isometric View of the Prototype Mecanum Drive



Top View of the Prototype Mecanum Drive



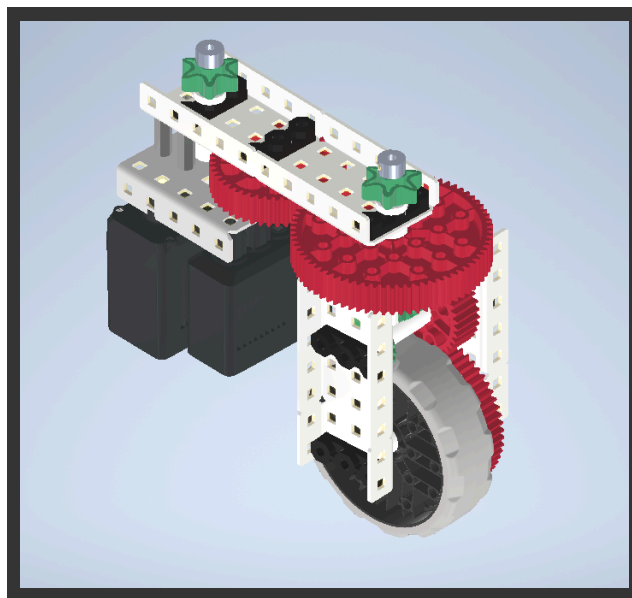
Front View of the Prototype Mecanum Drive



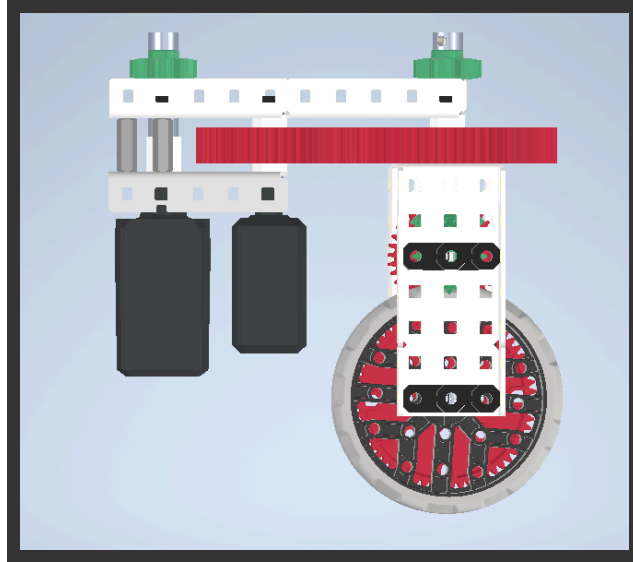
Side View of the Prototype Mecanum Drive

Before we could enter school to test this I created a Model for a Swerve Drive module:

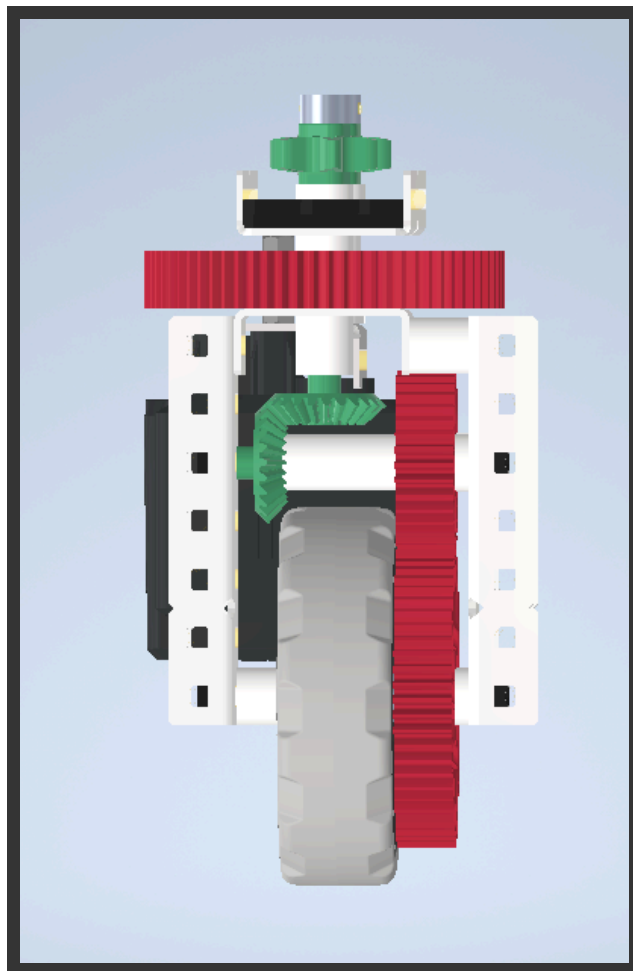
- Keeps design compact with motors below the frame
- 72 tooth gear is screwed to the frame so they spin together
- Circular insert within the gear to allow the drive shaft to turn
- Chain runs to connect the Drive Shaft to the 11w motor
- 5.5w motor used to turn module



Isometric View of the Prototype Swerve Drive Module



Side View of the Prototype Swerve Drive Module



Front View of the Prototype Swerve Drive Module

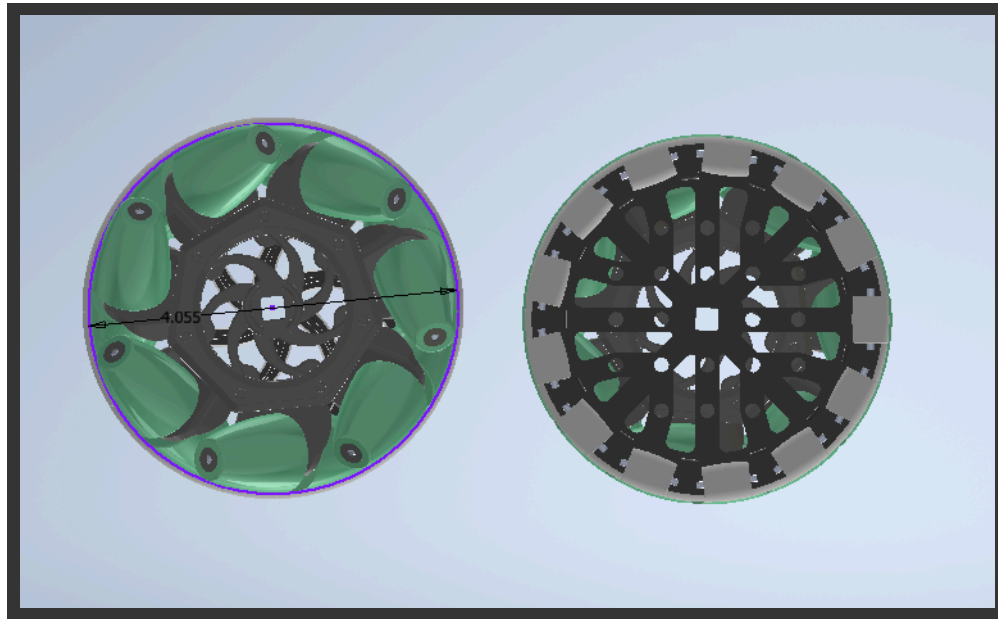


Note

It is unlikely any of these drives will be used as tank drives have proved superior for many games in a row. They simply serve as a way to practice building and design techniques and mechanisms before the next season. However, cataloging them is still important as the ideas learned from them could prove very important.



While Building the Mecanum Drive a large oversight was made. Vex wheels may be advertised in standard sizes like 4in but that is seldom the case. For the wheels various forum posts and the perdu vex sig robotic website placed both the older 4 in omni wheels and 4in mecanum wheels as having a 4.125in diameter. However once we built the drive we found the omni wheel to be slightly bigger. Going into inventor confirmed these as the Mecanum wheels measured .0625in smaller then the omni Wheels.



Comparison of Mecanum Wheels and both the new (right) and old (left) omni wheel diameters

This means that for now until we can get the newer omni Wheels which should be compatible with the mecanum wheels them alogn with the pto attached to them will be left out of the build. The older Wheels can not be used as they cause only one of the mecanum wheels to be in contact with the groudn which defeats the purpose of the drive.

