

0.1 Brainstorming (21.09.2015)

Time frame: 21.09.2015 17:00-21:00

Preview: Since this year FTC rules were published, every member of our team had carefully read them. Today we gathered together to discuss all the aspects of this year gameplay and think of how to get on with the most significant features of the game.

General aspects:

| Features | Solutions | Label |
|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|----------|
| Moving to the ramp is essential to achieve high score. | Robot's wheel base should be good at moving on the ramp. | chassis |
| Space between each two bars in 3-rd zone is wider than the standard TETRIX wheel diameter. | Using tracks or 3-4 wheels from each side of the robot will prevent robot from getting stuck. | chassis |
| It will take a lot of time to climb to the 3-rd zone of the ramp. | It is possible to deliver debris to the highest goal with elevator standing on the 2-nd zone instead of climbing to the 3-rd. | elevator |
| Goals for debris have a very little capacity. | It is more preferable to collect cubes than balls. That's why we need mechanism to prevent balls from collecting. | gripper |
| Pulling up costs 80 points. It's not difficult to realise then. | At least 1 DC motor should be reserved for pulling up. It is possible to grasp the pull-up bar with hook and lift to it by reeling the cable. | pull up |
| Moving over the inclined plane and pulling up require high moment on motors. However, the number of motors is limited. | Robot should be light enough to decrease the moment required for moving and, as a result, increase speed of moving. | weight |
| All the zones of red alliance are the mirror reflection of blue alliance's zones. | Robot should be symmetrical and capable of playing on both sides of field. | concept |
| Robot can grip 5 debris at once, when the maximal capacity of one bucket is 24 cubes. So, to fill one bucket robot has to repeat collecting and taking cubes to the goal 5 times per 1,5 minutes | Gripper for debris should be at the front side of the robot and extractor for scoring elements - from the back side. It will allow robot to go to the ramp backwards, so it won't need to turn around on the ramp before going down to collect debris. It will save some time. | concept |
| It's quite inconvenient to exchange ramps with your ally during the game. | We will negotiate with our ally about spheres of influence before each game. Additionally, there should be two autonomus programs for climbing onto both ramps. | strategy |
| The only main difficulty of this year autonomus period is that both robots in alliance have to fulfil the same tasks at the same place. So, there is a high risk of collisions between them. | A number of different programs for autonomus period are needed for easier adjustment to the ally's strategy. | strategy |
| It's not restricted to collect debris in autonomus period. | It will be useful to realise automatic collection of 5 cubes in autonomus period. At the conclusion of autonomus period the robot will remain on the ramp with 5 cubes and we will put them to the goal immediately | strategy |

Detailed explanation:

1. As we know from our previous FTC seasons experience, there are strict constraints for wheel bases can be used for climbing mountains. Firstly, omni and mecanum wheels are completely not suitable, because mecanum wheels can ride only on plain surface (when 2-nd and 3-rd zones have cross hurdles) and omni wheels have ability of undependable movement on small rollers so they behave very unstable on mountain. Various combinations of standard and omni wheels can't be used too, as in the 2-nd zone there are obstacles which can cause some wheels lose contact with ground and if the rest of wheels will behave differently, the whole robot would be unstable. In conclusion, we can use only standard wheels or tracks.

Additionally, wheel base should be symmetrical against central axis for stable climbing to the mountain. If we decided to climb 3-rd zone with standard wheels, we will have to put 3-4 wheels at the each side to avoid getting stuck on hurdles (the space between two hurdles is for about 14 cm, when the diameter of big TETRIX wheels is only 10 cm).



Рис. 1: possible wheel bases

2. To score in high zone goal from 2-nd zone robot should have a mechanism for delivering debris to the distance of 40 cm or more. Shooting debris is entirely unsuitable approach, because it's impossible to realise enough accuracy for stable scoring cubes and especially balls. Another way is elevator. There are three types of lifts which familiar to us: they're crank lift, scissor lift and retractable rails.

Scissor lift is not suitable for this year competition, because despite it's main advantage - the ability of extracting the longest distances of all - it's too difficult in development.

Crank lift allows to vary the angle of turning of each segment. However, it requires at least one DC motor or strong servo for every joint.

Retractable rails can only move along one axis. However, they require the least space and can be equipped by one DC motor (as all the motors are connected to the only reel, which winds the cable).

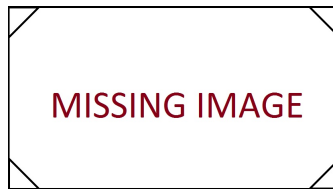


Рис. 2: types of elevators

3. The parameters of the box are $9 \times 5.75 \times 6.25$. So, it can contain at most 24 cubes (4 in length, 2 at width and 3 in depth). As for balls, there can't be scored over approximately 10 of them because of their inconvenient shape and ability of top balls to roll out of the box (especially from the upper box, which is turned on 50° from horizontal position).

This is the reason to implement mechanism for separating debris into cubes and balls. However, there are only 50 cubes on field (12.5 for one robot), so they will run out quickly, so the ability of collecting balls is required as well.

Additionally, we need to think of how to put cubes into boxes gently so as they will settle down in straight lines. It will allow entire filling boxes with cubes.

4. Solid constructions for pulling up will be too bulky because they have to be strong enough to withstand full weight of the robot. The more reliable and simple solution is steel cable with hook for grasping the bar on it's tail.

In second case the most difficult objective is to deliver hook to the bar, which can be solved by creating secondary lift for it (the main one is a lift for debris). Mechanism for shooting hook towards the bar is not suitable as it can be dangerous for operators and spectators (if the it will be accidentally activated during the match).

5. The main weight of the robot goes the battery and motors. The weight of the battery is 570g. We have two types of motors: standard TETRIX motor (207g) and "NeveRest 40" motor by AndyMark (334g). The complete control system (phone + controllers + power distributor) weigh about 700g.

Therefore, total weight of essential components varies from 2926g to 3942g (with 8 motors). With several beams (166g the longest), wheels (117g each) and other construction elements robot will weigh from 6 to 10kg.

In our primary calculations robot's weight will be accepted as 10kg. However, it is preferable to make robot as light as possible.

6. Wheel bases which are good at climbing mountains are usually less manevrou, than carriages with omni and mecanum wheels. This way, the less robot will turn, the more effective it will compete.

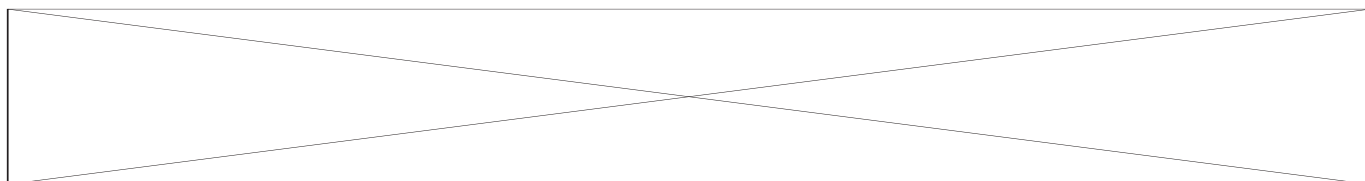
Accordind to this, it will be more convenient to realise construction that will allow robot to score debris without turning around. Robot can collect debris with gripper on it's front side while moving forward and then go backward to the ramp and score debris with the mechanism on it's back side.

Furthermore, it will be useful to attach one robot to one ramp in order to prevent them from committing extra movement. Although it seems that two robots can fill the top goal together two times faster, in fact they will just interfere with each other. So, it will be a good tactical step to negotiate with our ally before the mach which robot will operate with each mountain.

7. This year field is symmetric with respect to the diagonal. It means that all zones of one alliance are the mirror reflection of another. Consequently, the gameplay depends on which alliance you are playing for. So, the robot should be capable of executing equal tasks playing for each alliance. The major inconvenience cause releasing alpinists, as it requires two similar mechanisms from both sides, that will take 2 servos instead of 1. Mechanism For scoring debris should be summetrical to provide filling boxes from both sides of the ramp. Besides, autonomus program should be twoside as well.

Additional comments: For the next meeting we need to think of two issues:

1. which tasks our robot should be able to execute without loss of efficiency and
2. to set the priorities of performing tasks during the game.



0.2 Strategy discussing (22.09.2015)

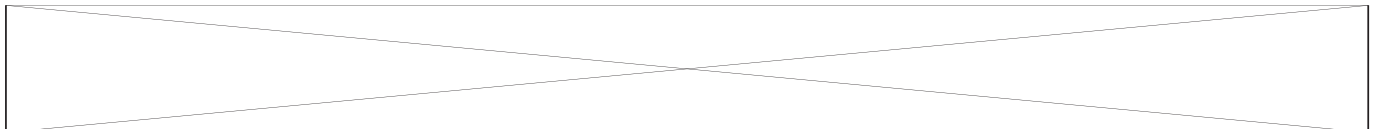
Time frame: 22.09.2015 17:00-21:00

Preview: Today we put the priorities during the building of the robot and performing tasks of the game.

Detailed explanation:

1. The tasks which robot must complete (We assume that robot can do everything. Tasks located in order of priority) :
 - 1.1. Autonomous period:
 - 1.1.1. Push the button and score climbers. It give 60 points (20 - button 10x2 - climbers in autonomous 10x2 - climbers in tele op).
 - 1.1.2. Ride to opposite mountain and collect balls and bricks. It help us to save a time because when start tele op we already have 5 bricks.
 - 1.1.3. Go to middle or high zone of the mountain. It give 40 (or 20) points. Additionally, we start driver control period near the top box. So we can put 5 bricks there immediately.
 - 1.2. Driver control period:
 - 1.2.1. Put elements that we collected in autonomous period to the top box.
 - 1.2.2. Go from the mountain and collect 5 bricks. We decided to collect only bricks because the balls take up much space in the box. So if we collect only bricks we can put more elements to one goal and get more points.
 - 1.2.3. Put 5 bricks to the top box. After that the top box most likely will be full. So we won't be able to put another five bricks.
 - 1.2.4. Collect and put 5 bricks to the middle box.
 - 1.2.5. Start moving to the crossbar and score climbers.
 - 1.2.6. Turn "all clear"signal.
 - 1.2.7. Pull-up.
2. Implementation of robot that can perform following tasks (tasks are in order of priority)
 - 2.1. Stable scoring to the middle box. This task is very simple and give a lot of points.
 - 2.2. Scoring to the high box. This task is more complex but gives more points.
 - 2.3. Releasing the climbers on the rope in driver control period. We can do it very fast and get 60 points but for scoring the top climber we must be able to climb to high zone.
 - 2.4. Scoring climbers in autonomous period. It is very easy task that give 40 points (as 4 bricks in the middle box).
 - 2.5. Riding to the high zone. It can give 40 points in autonomous period and 40 points in tele op.
 - 2.6. Pulling up. This task give the most number of points.
 - 2.7. Turning "all clear"signal. It gives us 20 points and our opponent lose 20 points.
 - 2.8. Pushing button. This task is difficult in terms of programming and gives only 20 points.

Additional comments: Task for the next meeting: to elaborate concept of the robot.



0.3 Concept discussing (24.09.2015 - 03.10.2015)

TIME FRAME: 24.09.2015 - 03.10.2015

PREVIEW: Objectives for current session are developing the concept of the robot and

CONCLUSIVE SOLUTIONS FOR MODULES:

| Module | Solution | Label |
|--------------------------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------|-----------|
| Carriage | U-shaped constrution opened from the front side. | chassis |
| Wheel base | 6 standard wheels with 6 DC motors. The center of gravity is between second pair of wheels; corner wheels are equidistant from the center of gravity. | chassis |
| Elevator for debris | Crank elevator with one degree of freedom. | elevator |
| Bucket for debris | | bucket |
| Separator for debris | | bucket |
| Rotating blades | | gripper |
| Slopes for collecting debris | Slopes on both sides of the bucket will increase the collecting area | gripper |
| Beam for scoring autonomus alpinists | L-shaped beam turning by servo. Alpinists placed in small bucket on the remote side of the beam. | alpinists |

SEPARATION TASKS BETWEEN COLLABORATORS:

| Collaborator | Modules | Label |
|---------------------|---------|--------------------|
| Wheel base | | chassis |
| Elevator and bucket | | elevator bucket |
| Gripper and slopes | | gripper |
| Beam for alpinists | | alpinists |

DAYS INSIDE SESSION:

0.3.1 24.09.2015

Time frame: 17:00-21:30

Preview: The main purpose for current meeting was to figure out how the modules of the robot should look and how they will work.

Modules:

| Module | Solution | Label |
|--------------------------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------|-----------|
| Wheel base | 6 standard wheels with 6 DC motors. The center of gravity is between second pair of wheels; corner wheels are equidistant from the center of gravity. | chassis |
| Heaviness | Robot should be as light as possible to afford gear ratio for speed 2:1 on drive motors. | chassis |
| Elevator for debris | Crank elevator with one degree of freedom. | elevator |
| Bucket for debris | Bucket with turning cover which will close entry inside the bucket to prevent scoring elements from accidental falling out | bucket |
| Slopes for collecting debris | To increase collecting area on both sides of the bucket will be placed slopes | gripper |
| Separator for debris | Turnable beam before the bucket, which prevents balls from getting into the bucket in it's lower position (5cm from floor). | gripper |
| Beam for scoring autonomus alpinists | L-shaped beam turning by servo. Alpinists placed in small bucket on the remote side of the beam. | alpinists |

Detailed explanation:

1. Detailed explanation...

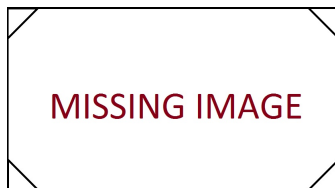


Рис. 3:

2. Detailed explanation...

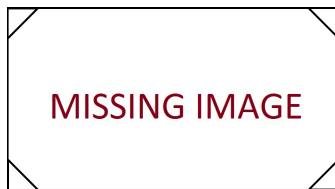
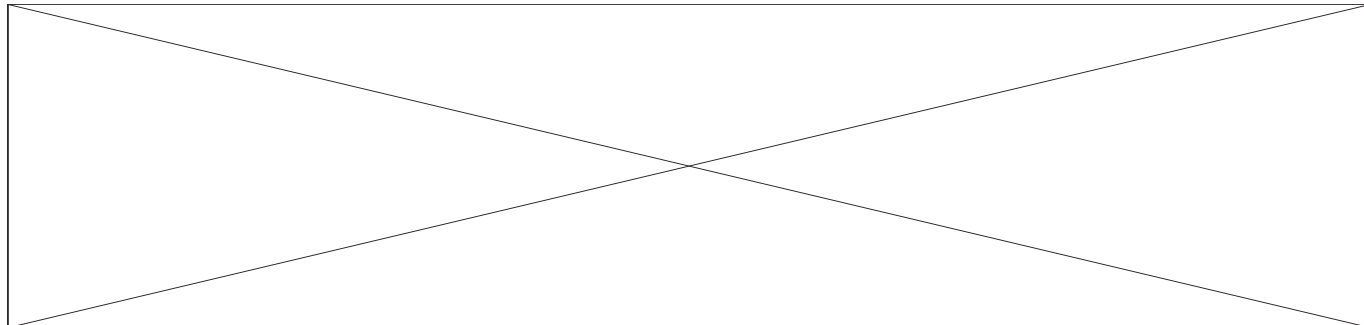


Рис. 4:

Additional comments: The next meeting we will continue developing concept.



0.3.2 26.09.2015**Time frame:** 16:00-21:30**Preview:** The purpose for current meeting was to develop ideas were invented last meeting.**Modules:**

| Module | Solution | Label |
|---------------------------------------|----------------------------------------------------------------------|-----------|
| Bucket for debris | | bucket |
| Debris separator and cover for bucket | | bucket |
| Crank elevator | | elevator |
| Beam for scoring alpinists | | alpinists |
| Gripper for debris | Axis with 2 rotating blades ahead of the bucket for grabbing debris. | gripper |

Detailed explanation:

1. Detailed explanation...

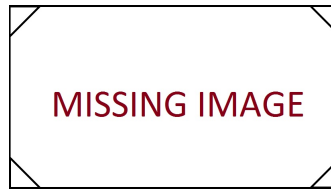
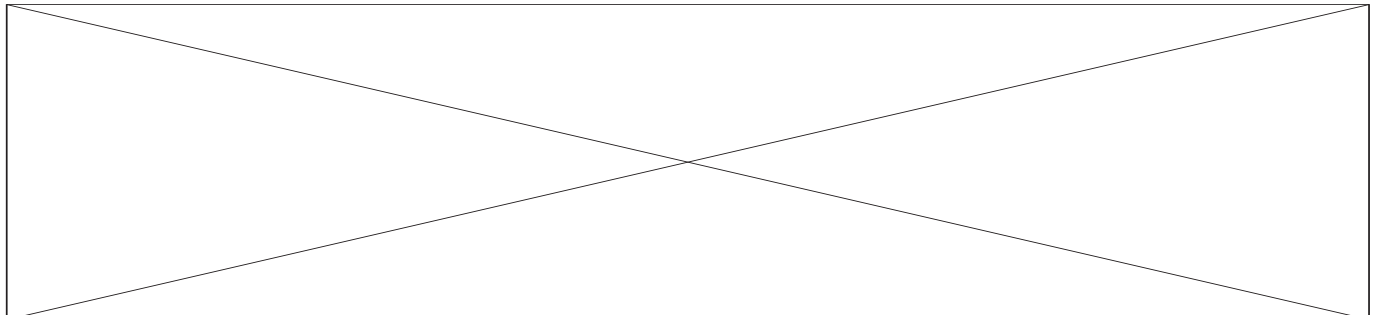


Рис. 5:

2. Detailed explanation...



Рис. 6:

Additional comments: The next meeting we need to revise all the aspects of concept and correct it.

0.3.3 28.09.2015**Time frame:** 17:00-21:30**Preview:** The purpose for current meeting was to revise all our previous ideas and reveal weaknesses. Then correct concept.**Weak points**

| Weak point | Solution | Label |
|---------------------------------------------------------|---------------------------------------------------------------------------------------------------------------------------|---------|
| Gear ratio 2:1 on wheels can be not enough for climbing | It will be installed gear ratio 1:1 at first. If tests of gear 2:1 will be successful, it will be installed on the robot. | robot |
| Shape of the bucket | | program |
| Shape of the beam for scoring alpinists | | program |

Detailed explanation:

1. Detailed explanation...

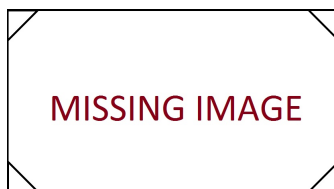


Рис. 7:

2. Detailed explanation...

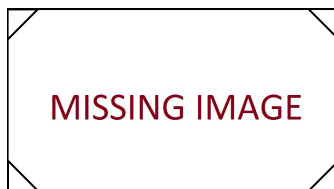
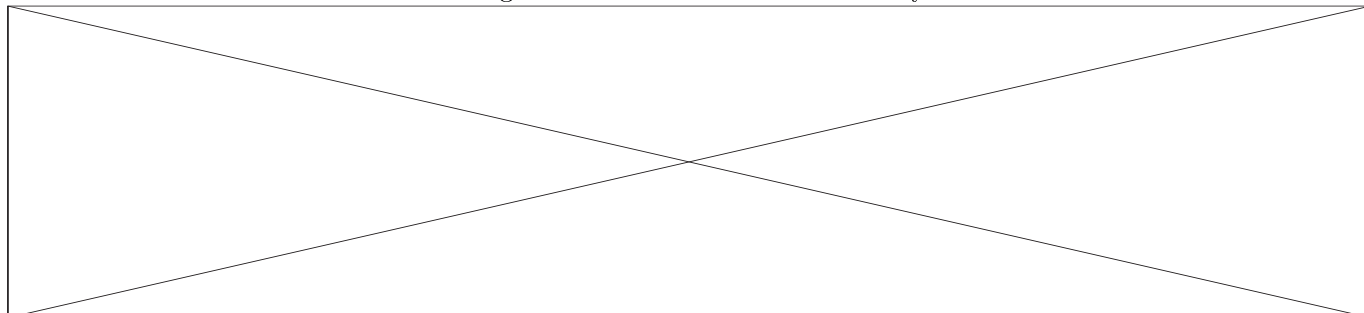


Рис. 8:

Additional comments: The next meeting we will structure ideas into a system.

0.3.4 01.10.2015

Time frame: 17:00-21:30

Preview: The purpose for current meeting was creating structural layout of the robot in CAD Creo Parametric 3.0.

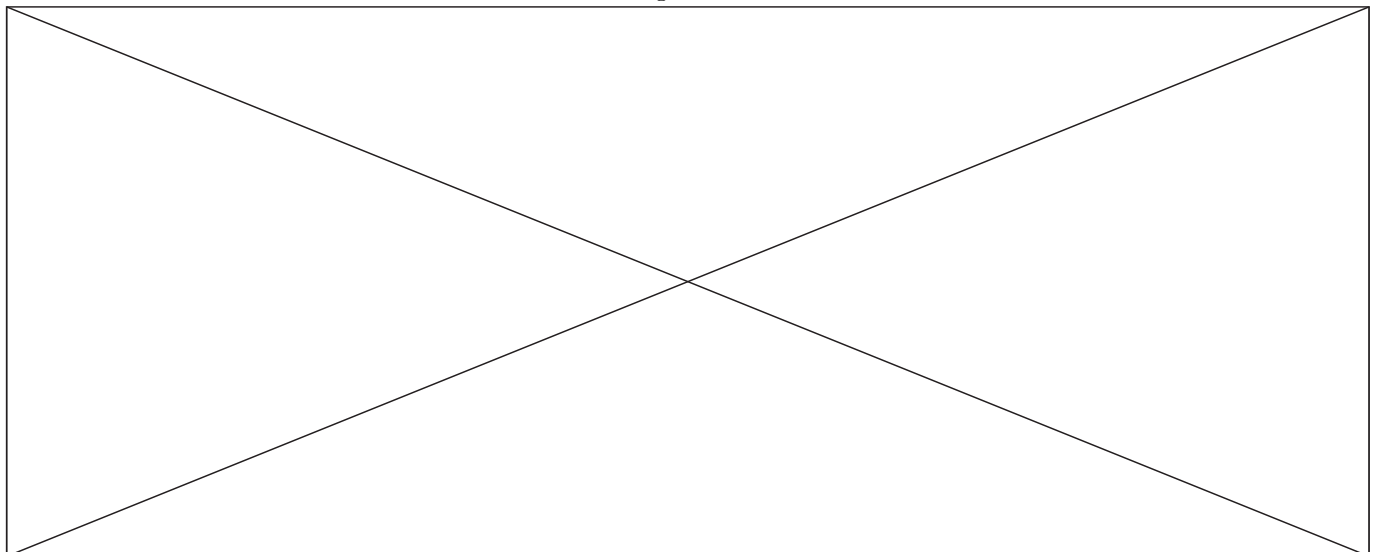
Detailed explanation:

1. We made a structural model of the robot. The whole construction was divided into particular modules. They are:
 - 1.1. Chassis - carrying base and wheels mounted on it.
 - 1.2. Bucket - container for debris.
 - 1.3. Elevator - mechanism for lifting bucket.
 - 1.4. Gripper - mechanism for collecting debris.
 - 1.5. MSA - mechanism for scoring autonomus alpinists.



Рис. 9: Structural model of the robot

Additional comments: The task for the next meeting is to summarize our ideas for each module.



0.3.5 03.10.2015

Time frame: 16:00-21:30

Preview: The purpose for current meeting was to divide all construction works into 4 groups (one group for one teammate) to provide elaborating modules in parallel. After that, we wrote technical specification for each group of modules to help collaborators follow the requirements.

Technical specifications for modules:

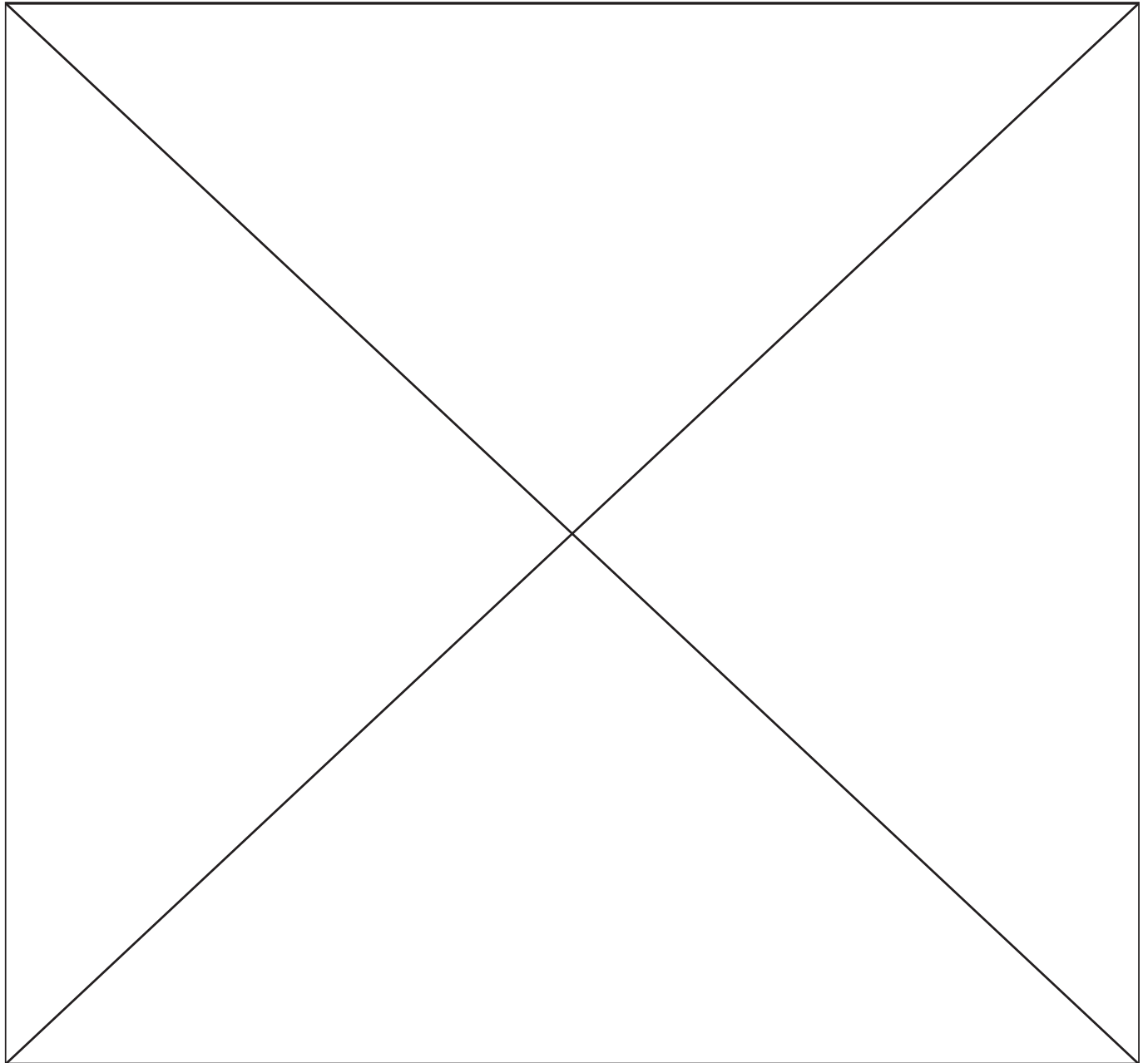
1. Chassis
 - 1.1. Carriage consists of two lengthwise beams 41.5cm connected at the back side. All other modules will be mounted to this base.
 - 1.2. Wheel base consists of 3 pairs of standard wheels. All wheels at one side are linked to each other and move dependently.
 - 1.3. Wheel base is powered by 6 dc motors (3 at one side).
 - 1.4. Motors should not interfere with bucket which will be placed in the forward half of the robot.
 - 1.5. There should be no construction elements except wheels that can touch the surface while climbing the ramp.
2. Elevator
 - 2.1. Elevator consists of 2 static beams fixed on the base and one pivoting with bucket on it.
 - 2.2. Turnable beam rotates around the axis on top of the static beams. It's rotation powered by 1 dc motor with gear ratio 1:3.
 - 2.3. Length of the elevator should be enough for scoring debris into all boxes without climbing to the 3-rd zone.
3. Bucket
 - 3.1. Bucket should be fixed to the turning beam of elevator stationary.
 - 3.2. Free space inside the bucket should be 10-14cm at width, 15-17cm in length and 7cm in height. It should be capacious enough for containing 5 cubes of 3 balls.
 - 3.3. The back side of the bucket can be narrower to prevent collecting more than 5 cubes at once (cubes will settle as $2 + 2 + 1$).
 - 3.4. Bucket's movement should not interfere with gripper for debris.
 - 3.5. Entrance hole of the bucket should have the same height and width, as the internal space.
 - 3.6. Bucket should have a turning flap above the entrance which can prevent balls from scoring on demand. Additionally, the flap will stop debris from falling out of the bucket when it will be overturned.
4. Gripper
 - 4.1. Gripper consists of 2 rotating blades, mounted to axis at an angle 180° to each other.
 - 4.2. Gripper is powered by 1 or 2 continuous rotating servos.
 - 4.3. Gripper is placed ahead the bucket. Width of blades should match with the entrance of the bucket.
 - 4.4. Space between axis and field enough for unhindered passage of balls.
 - 4.5. Gripper should not make any obstacles for bucket's moving.
 - 4.6. At both sides of the blade's working area placed slopes, which are tapering to the bucket.
5. Alpinists
 - 5.1. Mechanism for scoring autonomus alpinists will be placed at the forward side of robot. It's definite position will be determined after discussion of autonomus strategy.

- 5.2. Mechanism consists of L-shaped beam powered by standard servo.
- 5.3. At the end of beam placed a bucket for 2 alpinists.
- 5.4. Module should not interfere with gameplay after the autonomus period ends.

Responsibilities for each module:

- 1. Carriage and wheel base -
- 2. Bucket and elevator -
- 3. Gripper with slopes -
- 4. Mechanism for scoring alpinists -

Additional comments: Now our team is ready to proceed to the next objective: designing modules.



0.4 Lift and bucket for debris

0.4.1 Lift

The lift consists of two beams. One beam is stationary and it is fixed vertically on the back part of the robot. The second beam turns by DC motor that mounted at the top of stationary beam. The length of beams must allow to score debris to high goal from the middle zone and to middle goal from low zone. For estimating optimal length of beams it was made drawing in GeoGebra.

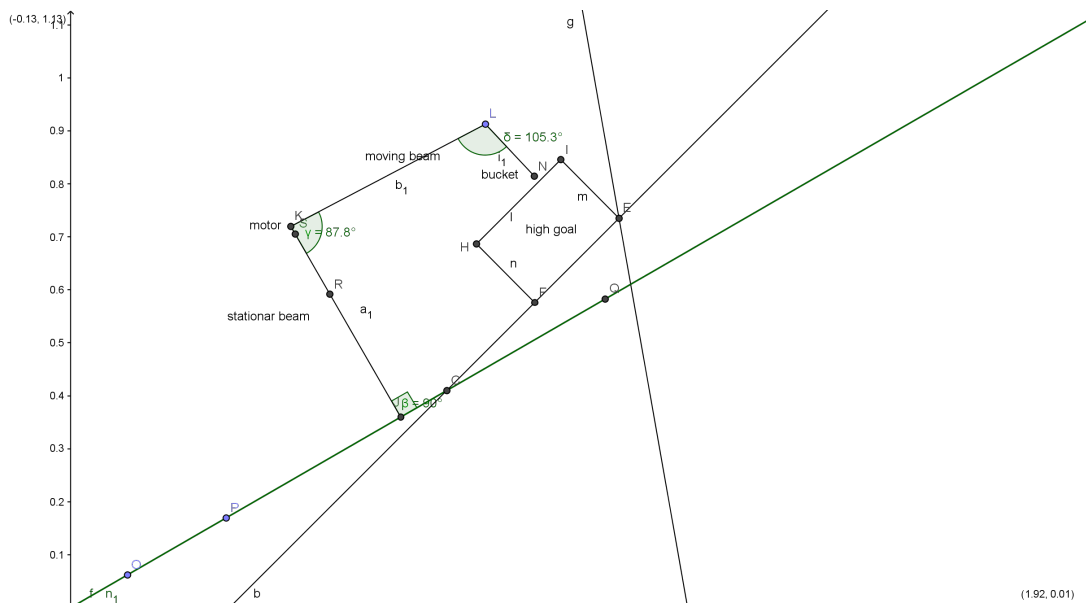


Рис. 10: Drawing of the lift

0.4.2 Bucket

The bucket's size allow to fit 3 cubes and 2 balls. For estimating optimal size and form it was made drawing in GeoGebra.

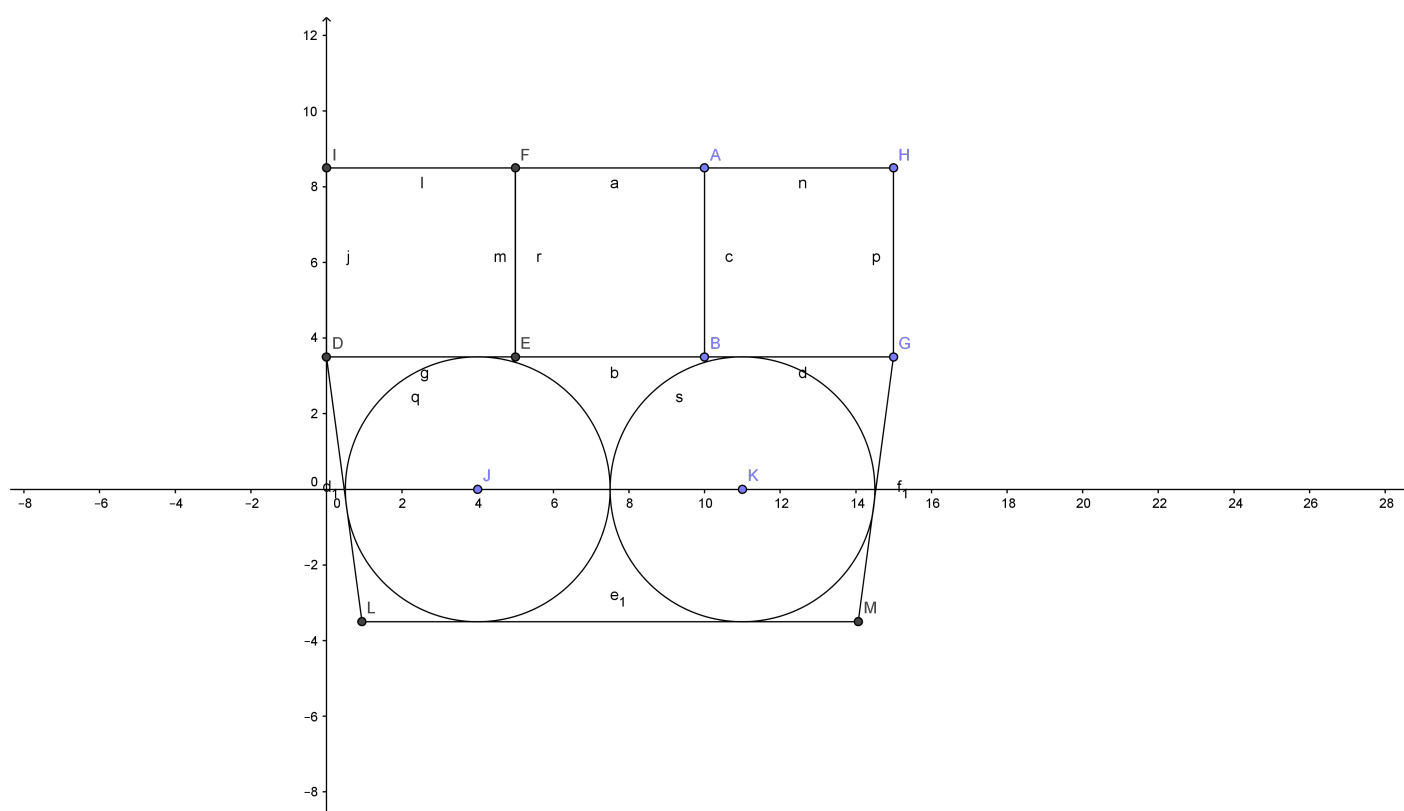
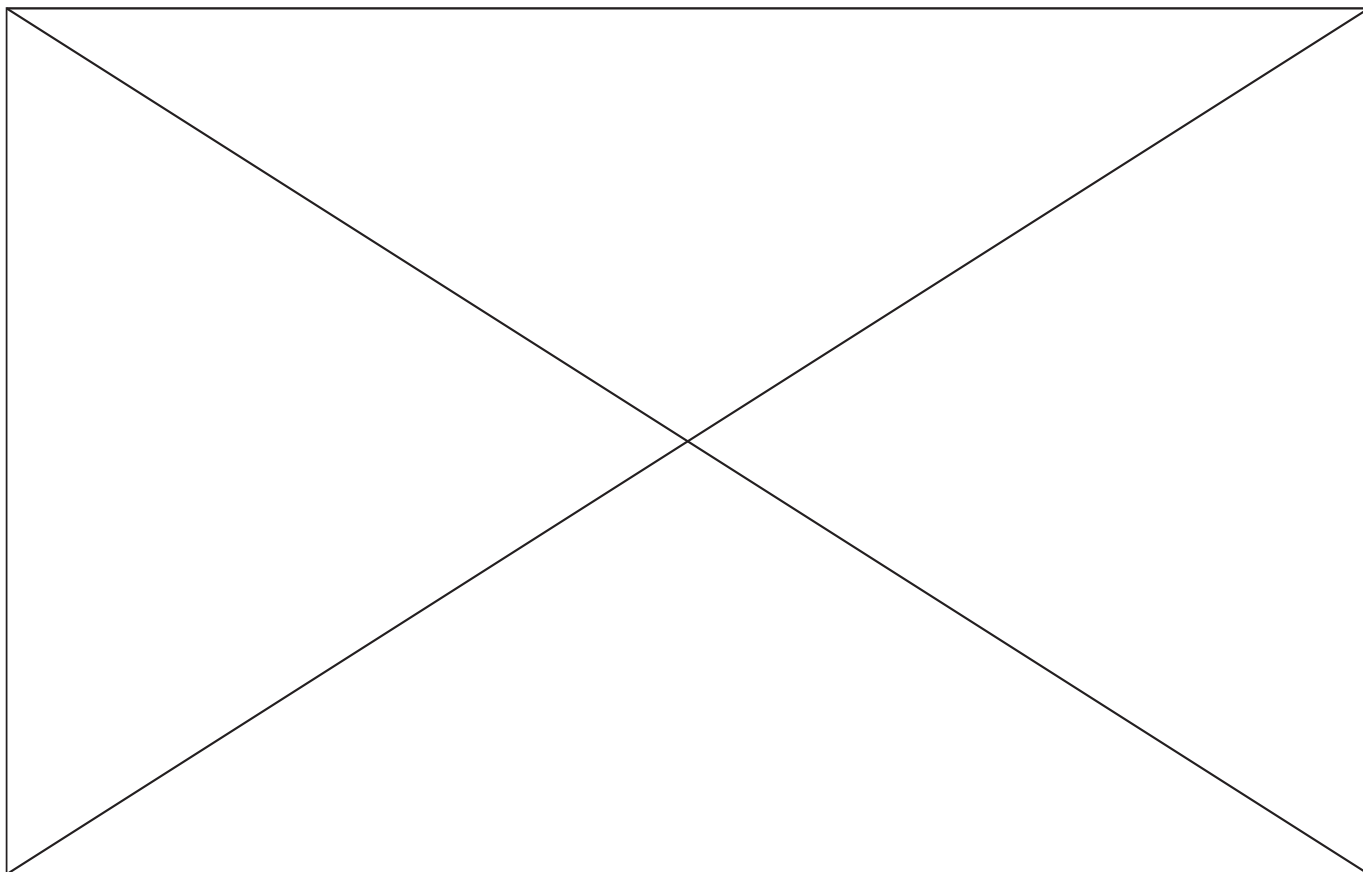


Рис. 11: Drawing of the bucket



1 Thanks and prospects

We enjoyed working on a custom and non-standard project, which, besides its technical aspect, included working with new people who shared our values of friendship and mutual understanding.

Our team is planning to continue doing robotics, setting new goals for ourselves in order to improve. This is our first year taking part in FTC and we will participate next year as well. If we don't realize ourselves this year, we'll look at all our mistakes, correct them, and perform a lot better next year.

In any case, we are ready to learn new things, improve ourselves and expand our skills.

None of us know for sure what we want to do in the future, but we are certain that our experience will be very valuable to us.

Our thanks go to the company FIRST for organizing this competition, which we are very happy to be participating in. We appreciate this wonderful opportunity to test ourselves and learn something new and wish them success and growth in their future endeavors.

Also we thank our sponsors: company PTC and its Russian representative "Irisoft" and charitable foundation "Finist" for their support. Also we thank Physics-Mathematics Lyceum 30 and its director Alexey Tretyakov for providing comfortable conditions for preparation to competition.

Team PML 30 φ

