Ian Johnston – Group 8 – milestone 4.

For this milestone I rebuilt the robot I improved the motor spacing decreasing the friction. I also built a top on the robot with a much more powerful kicker (which can now kick the length of the pitch).

I also tried to implement an update to the nav code that gets it to look at future points as well as the next one, however I've not managed to get it working yet.

Finally I did a PCB layout for the Arduino which should make it smaller and thus fit inside the robot while being much more robust.

I feel a 3 would be a fair score for my contribution.

I believe RW deserves a 4 as he has been working tirelessly to get the AI working.

I think the main thing we should do for the next friendly is update the nav to move along the path the AI gives it rather then just looking at the first point on the path. This would allow us to run the AI separately from the vision and the nav which has 2 benefits. 1) the AI has more time to do its stuff 2) Lets us run the Vision/nav at a higher frequency meaning it should be more accurate while moving.