Andrew and Cyrus met on Saturday during our Winter Break.

Cyrus worked on the new robot and finished its drive train. He named the robot “Blam Bot.” Andrew programmed the robot to make it move. However, the robot moved too quickly. The problem was with its gear ratio. It needed to be adjusted for torque instead of speed if we wanted it to be able to carry multiple goals, carry a mobile goal up a balancing platform, and have better control.

Andrew worked on the autonomous period of the Moby robot. There are three different methods for facing the autonomous period. The first method is to program what the bot does exactly. It will require fine tuning to make it move well. This would allow the robot to move according to specific instructions to the best of its ability. However, the field could vary. The second method is to record the robot being driven. It will require less time to fine tune the robot, but it does not allow the robot to be driven at full speed as when recording, the driver will need to be carefull. The field also varies. The third robot is to use a vision sensor. The robot will detect where the mobile goals, rings, and other robots are and by using an algorithm, it will find the most efficient way to score points during the autonomous period.

Cyrus took the robot home to work on the arms. We plan on meeting again during Winter Break to work on Blam Bot and the vision sensors before our next official meeting with the rest of the team next year. Happy Holidays.