



WPI

NSF Workshop Assembling your Romi

Last modification: January 3, 2022

1 Introduction

For these activities, you will be using Pololu's Romi robot platform, customized with a lifter assembly and several sensors. We arranged for Pololu to pre-solder headers onto the Romi Control Board, so assembly consists of putting some robot parts together, attaching the lifter arm, and wiring the components. Part of the activities later is to "optimize" the lifter arm to some extent – here we show you a nominal configuration.

2 Assembly

2.1 Materials and tools

- A Bill of Materials is found in Appendix [3.1](#).
- Small Phillips head screwdriver.
- A small pair of needle-nose pliers for holding nuts in place while assembling.
- **Note.** One size standoff (the shortest) is has M2.5 threading, whereas all of the other standoffs are threaded 2-56. You should discard the M2.5 standoffs – none of the provided screws or nuts will work with it.

2.2 Assembling the Romi

Procedure

1. **Build the basic Romi.** Referring to [the Romi User's Guide](#), build the Romi base. You should browse the first three pages of the User's Guide and then do the build according to [Assembling the Romi Chassis](#). Note that no soldering is necessary, so you can skip steps 1-3 and step 5 of the assembly instructions – we've done that for you!

Solution:

Install a rubber band (not provided) as shown in Step 12 of the Pololu build instructions. We typically leave that step out of the student instructions so that we can later discuss “incidental interactions” when students lift up heavy objects and discover that their line sensor readings change dramatically due to sag in the front end. For the purpose of this workshop, it is more expedient to put it in now, since it will be more difficult to do so after the breadboard has been installed.

2. **Add the line sensor.** Using (2) 3/4" standoffs, attach the line sensor to the front of the robot, as shown in Figure 1. Arrange is so that screws are on the bottom and nuts on the top so that the extra screw length doesn't drag on the ground.

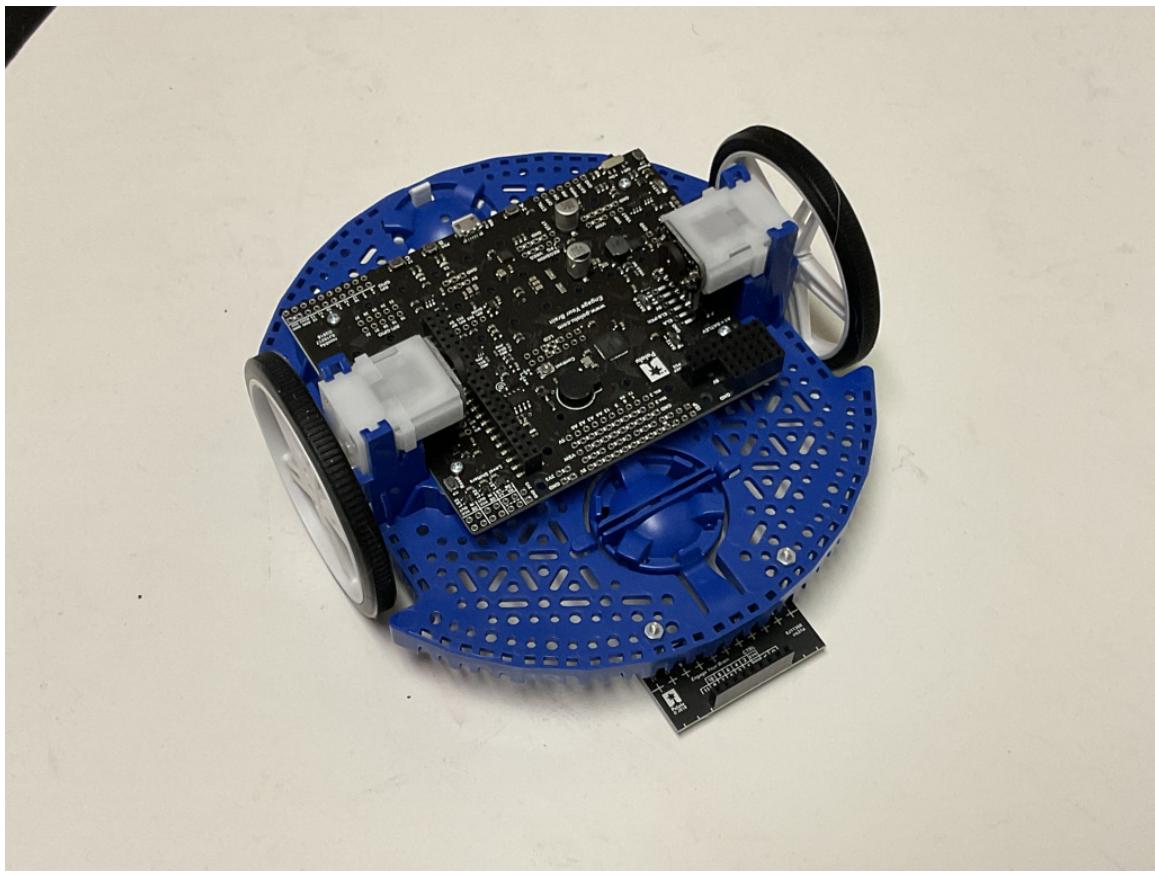


Figure 1: Romi base with line sensor attached.

At this point, you should pause and install an integrated development environment. A “Hello, World” activity, along with instructions for installing an IDE can be found in the [“Hello, World” activity](#).

2.3 Assembling the lifter arm

We have provided one copy of a lifter assembly for these activities. To do the activities with multiple robots, you will need a lifter assembly for each robot. A good activity is for students to 3d print

their own arms, and we provide [the .stl files](#) for you to print if you choose. We can also provide the SolidWorks files, upon request. If you don't have access to a 3d printer, additional arm assemblies can be sent to you with a few weeks notice.

The instructions below are for a nominal arm configuration. One of the later activities includes determining a better arm configuration and reconfiguring the arm. As such, we do not give specific instructions, as the exact configuration isn't important. The configuration shown in the figures is a good place to start.

Note: We have found that motor vibrations and driving tend to cause the nuts to work themselves loose over time. Be sure to tighten screws and nuts well and check/tighten them periodically.

Keep in mind that not every 3d print is the same – you may need to clean out support material or ream out a hole with a small screwdriver. Figure 2 shows the 3d printed parts for the arm assembly. You may have also received a mount for the ultrasonic rangefinder – we find that it is easier to simply mount the rangefinder in a breadboard. If you choose to use the mount, you may have to file out the holes to match your sensor.

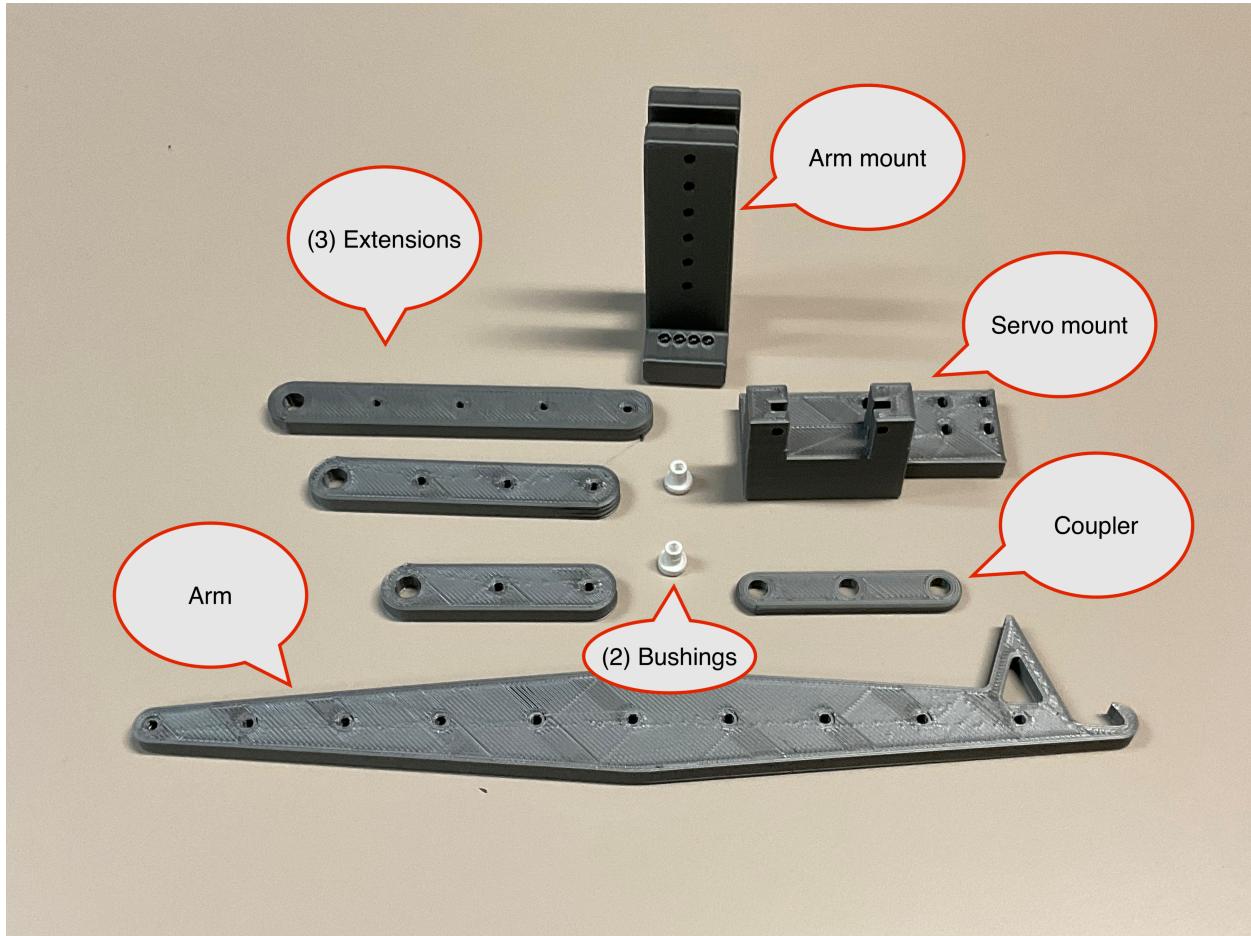


Figure 2: Parts for the arm assembly.

Procedure

1. Install the 1" and 1 1/2" standoffs on the expansion plate, as shown in Figure 3. Not every hole on the expansion plate lines up with a hole on the Romi base, so take care to put the standoffs in the holes shown. Test the alignment with the Romi base, but don't attach it yet – you'll want to attach the servo and arm mounts first.



Figure 3: Expansion plate with standoffs installed.

2. Attach the servo and arm mounts to the expansion plate with 3/4" screws. Relative alignment is important so that the coupler can connect the servo horn to the arm. Figure 8 shows what you are working towards. Figure 4 shows a good starting configuration for the mounts.

Some participants have noted that the pictured position of the screws can interfere with one of the motors. The arrow in the image indicates a better location for the screw.

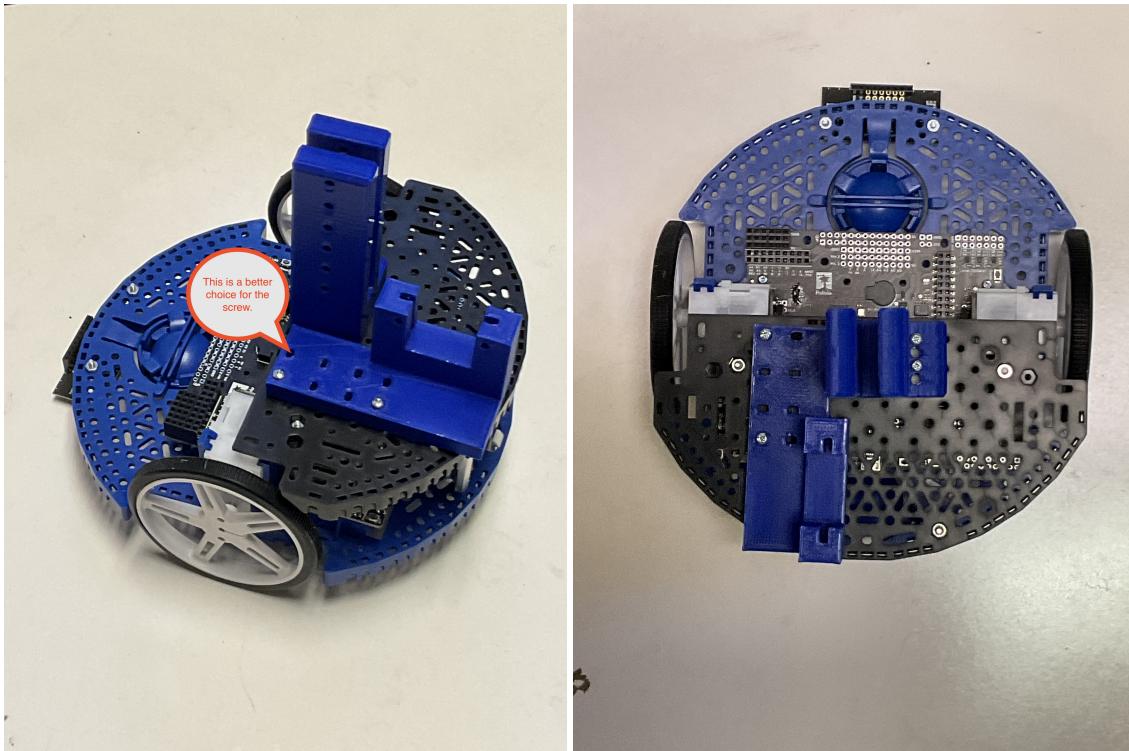


Figure 4: Servo and arm mounts mounted. Once you install the mounts, you can attach the expansion plate to the base, as shown in this figure.

3. Using 3/4" screws, mount the servo in the servo bracket. Be careful that the screw doesn't damage the wires coming out of the servo. Mount the horn on the servo using the smallest screw in the package of servo parts. You will want to attach the horn so that it ranges from straight up to straight down. Figure 5 shows the horn at the upward extreme. You can use the horn to gently drive the servo to one extreme or the other so you can properly align it.

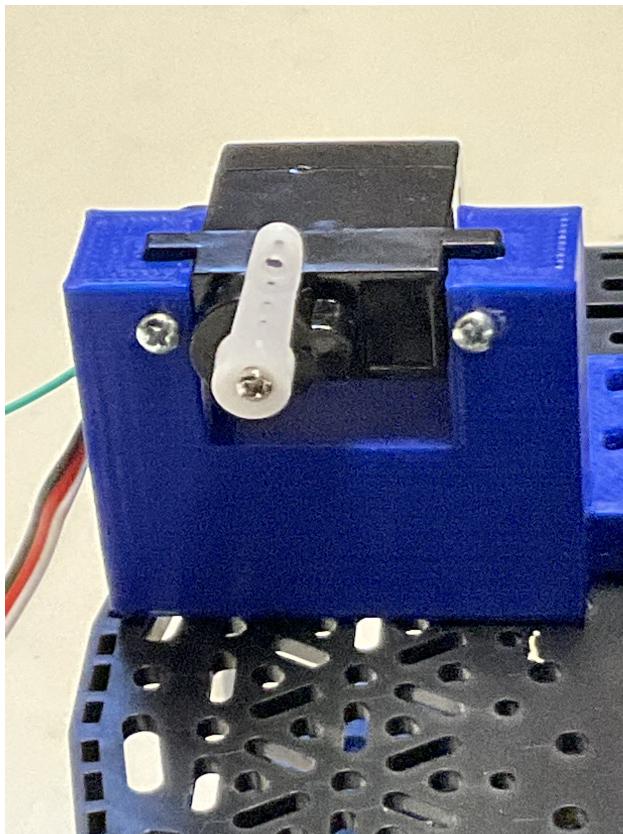


Figure 5: Servo with horn mounted.

4. Attach the arm to the arm mount with a 1 1/4" screw as shown in Figure 6.

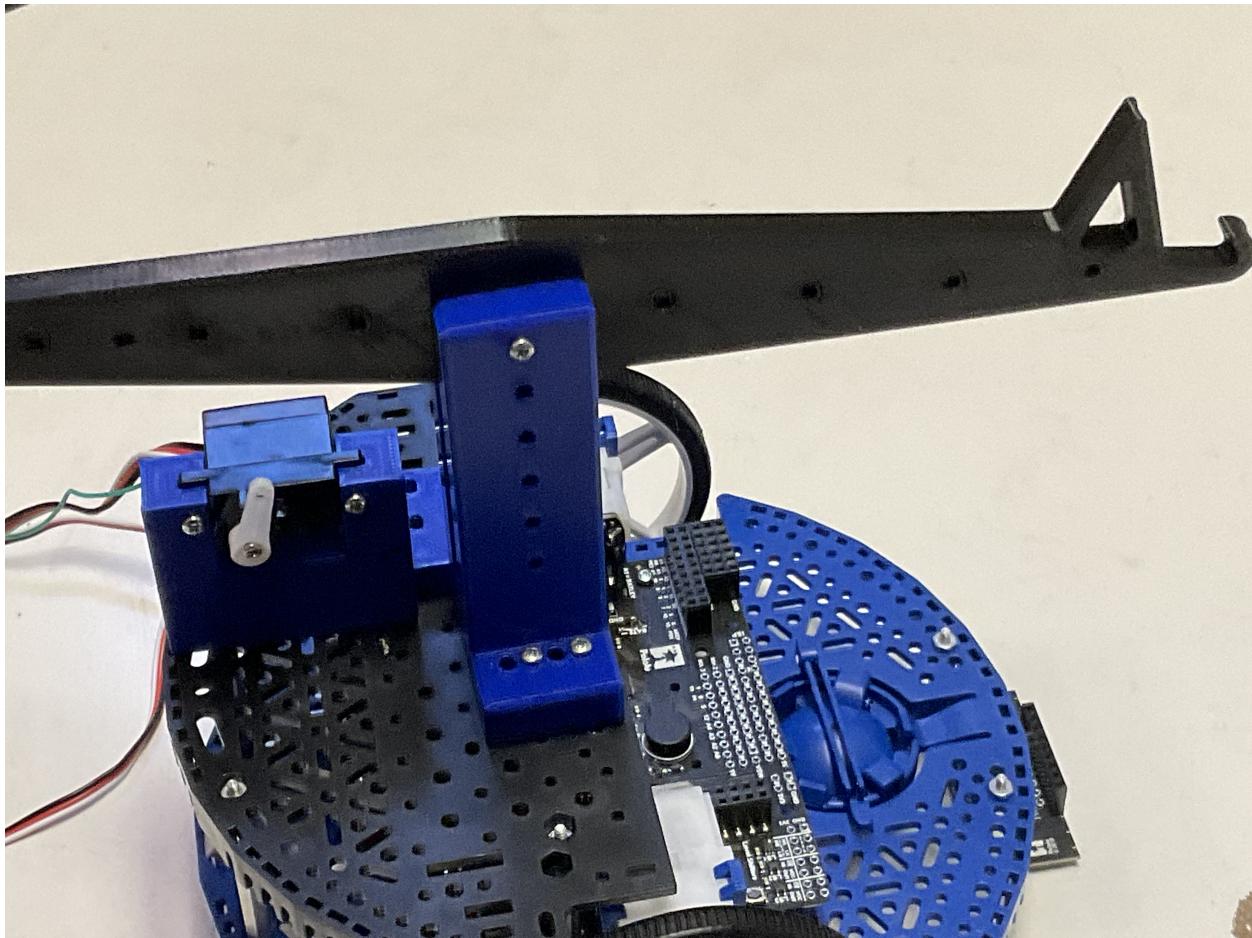


Figure 6: Arm attachment.

5. Using 3/4" screws and the provided bushings, attach the coupler to the servo horn and arm, as shown in Figure 7. Use the slightly larger hole near the end of the horn – the screw will be a tight fit, so be gentle when screwing the couple on. You will want to screw from the horn side so that the excess screw length doesn't interfere with the servo motion.

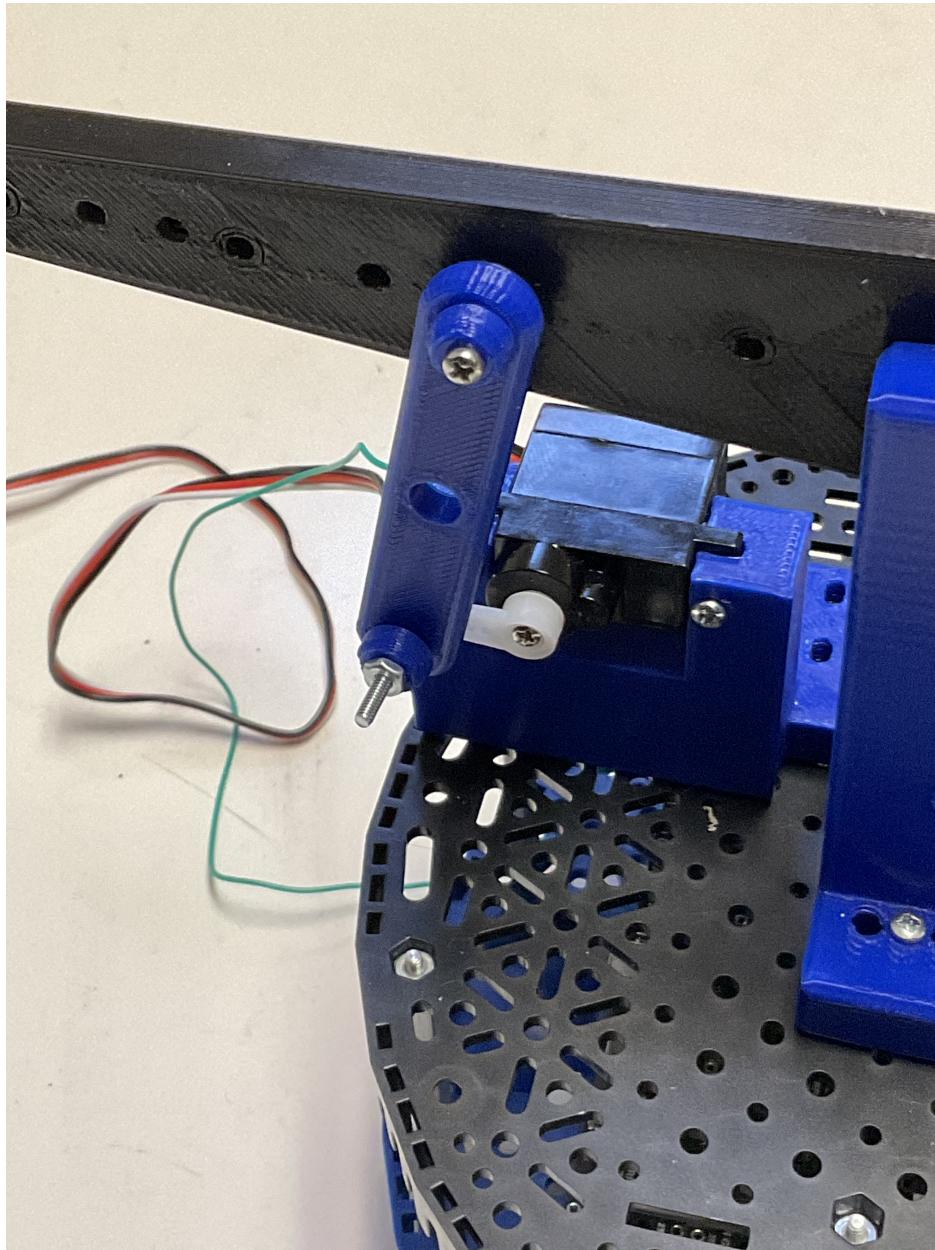


Figure 7: Coupler attachment.

6. Attach the expansion plate/arm assembly to the Romi base, as shown in Figure 8. Note that some of the screws screw in from the battery compartment.

7. Wiring for the servo is described below.

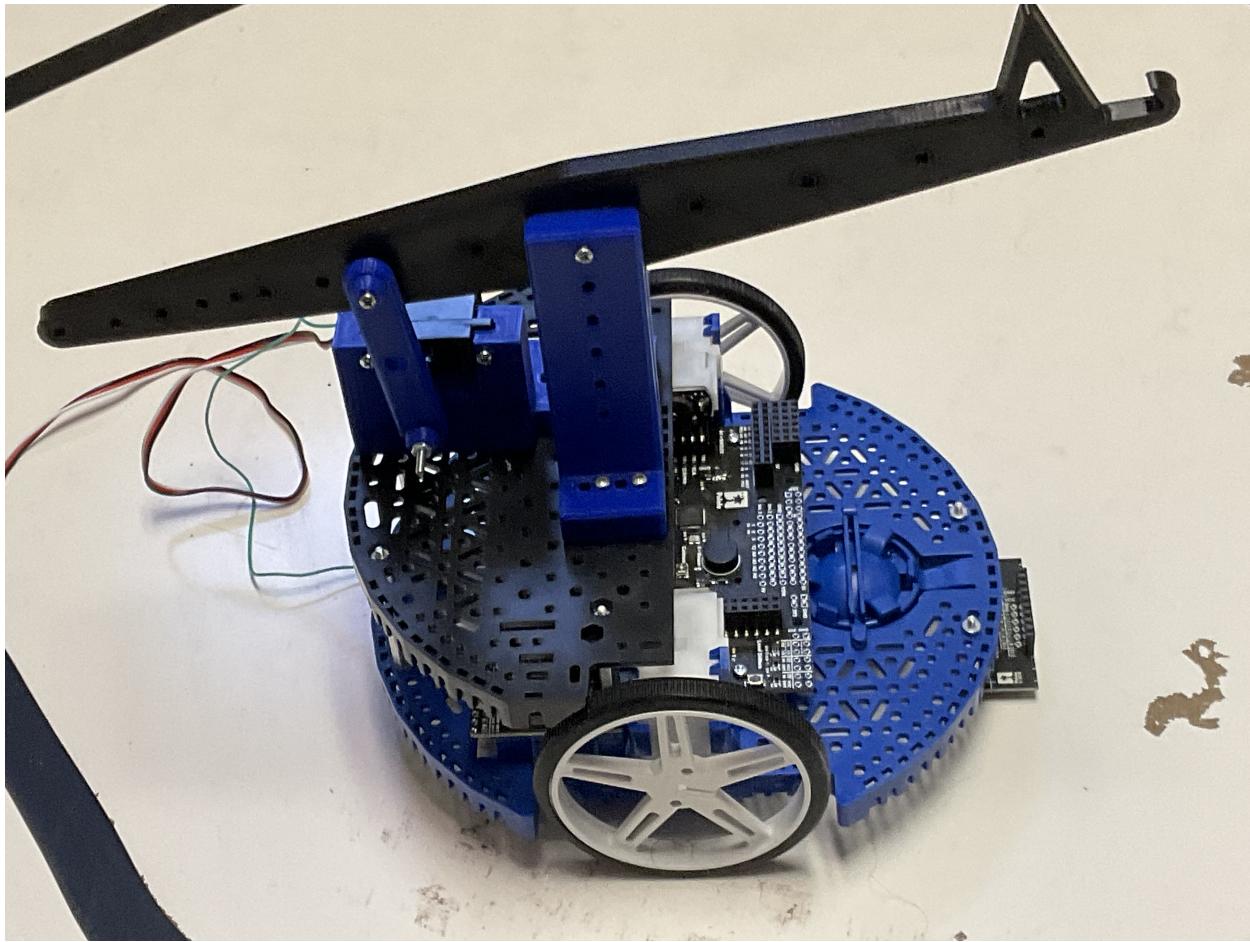


Figure 8: Romi with arm assembly complete.

2.4 Attaching the breadboard and wiring.

To simplify the wiring of components, we have pre-soldered headers on the front left corner of the Romi Control Board. For some components (e.g., the line sensor), it may be easiest to wire them directly to the sockets, for others, it may be easiest to use a breadboard (the servo motor, ultrasonic rangefinder).

Solution: Note that there are several options for mounting the breadboard, and each location has advantages and disadvantages. We show the breadboard mounted to the front of the Romi, which makes mounting the ultrasonic rangefinder easier, since it fits directly in the breadboard. Note, however, that this position interferes with the nominal motion of the lifter arm. While not originally intended, we have left the design as-is to give students a chance to discuss pros and cons of various positions for the arm and breadboard. “Reaching over” reduces the range of the arm. Positioning the arm off the rear of the chassis requires a 180 degree turn before picking up a container. Moving the breadboard requires re-thinking how to mount the ultrasonic rangefinder. Other options have advantages and disadvantages.

We show the breadboard mounted on the front, which is good for getting started.

Need a tutorial on how to use a breadboard? [Here is a good tutorial](#). Or here is a [video](#).

Figure 11 (at the end of this section) shows an annotated version of [the control board](#).

Procedure

1. Attach your breadboard to the Romi.

- Using the plastic tubing in your kit, cut (2) 1/4" lengths to be used as spacers. Using 3/4" screws, mount the breadboard to the base with the spacer between the breadboard and the chassis, as shown in Figure 9. Alternatively, you can just use tape or a rubber band to hold the breadboard to the Romi, but do not remove the backing paper on the breadboard – you’ll never get it off if you want to move it later!

Solution: Unfortunately, we didn’t realize until too late that the short standoffs that come with the Romi Control Board have a different threading than the screws. Set them aside.

- Using the provided wires, connect the 5V socket on the Romi Control Board to the ‘+’ power rail on the breadboard. Connect GND to the ‘-’ rail. Refer to [the pin diagram for the Romi](#) for which pins are where.

2. Connect the ultrasonic rangefinder.

- Insert the ultrasonic rangefinder such that it is pointing forward. Connect Vcc on the rangefinder to the ‘+’ rail and Gnd to the ‘-’ rail. Connect the Echo pin to pin 11 on the Romi. Connect the Trig pin to pin 4.

3. Connect the IR receiver.

- Insert the IR receiver such that it is pointing forward. Connect Vcc on the rangefinder to the ‘+’ rail and Gnd to the ‘-’ rail. Connect the OUT pin to pin 1 on the Romi. The pinout for the sensor can be found on the first page of [the datasheet](#).

4. Connect the servo.

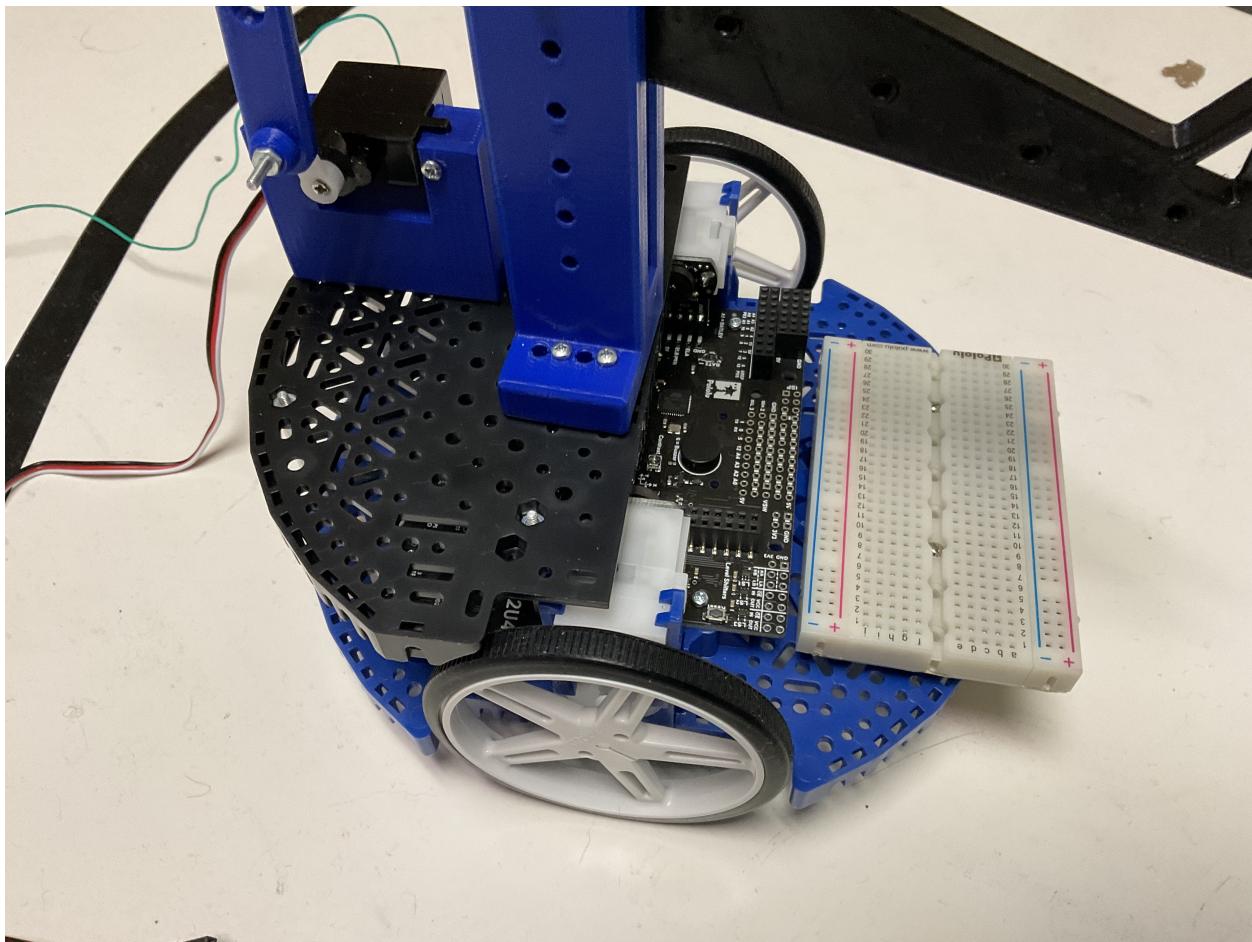


Figure 9: Romi with breadboard mounted.

- (a) Break off four of the breakaway pins and connect the servo wires to the breadboard. Use a wire to connect the red wire of the servo to the '+' rail and the black wire to the '-' rail.
 - (b) Use a wire to connect the white servo wire to pin 5. You can leave the green wire on the servo disconnected.
5. Connect the line sensor (reflectance) array. Though the line sensor array has six sensing elements, we will only use two of them for now (you may use a third later).
- (a) Wire the Vcc and Gnd on the line sensor array to the '+' and '-' rails. Connect any two sensor elements to A3 and A4 on the Romi Control Board. It's probably easiest to just connect them directly, though you can go through the breadboard, if you wish.

Figure 10 shows the complete robot, with wiring.

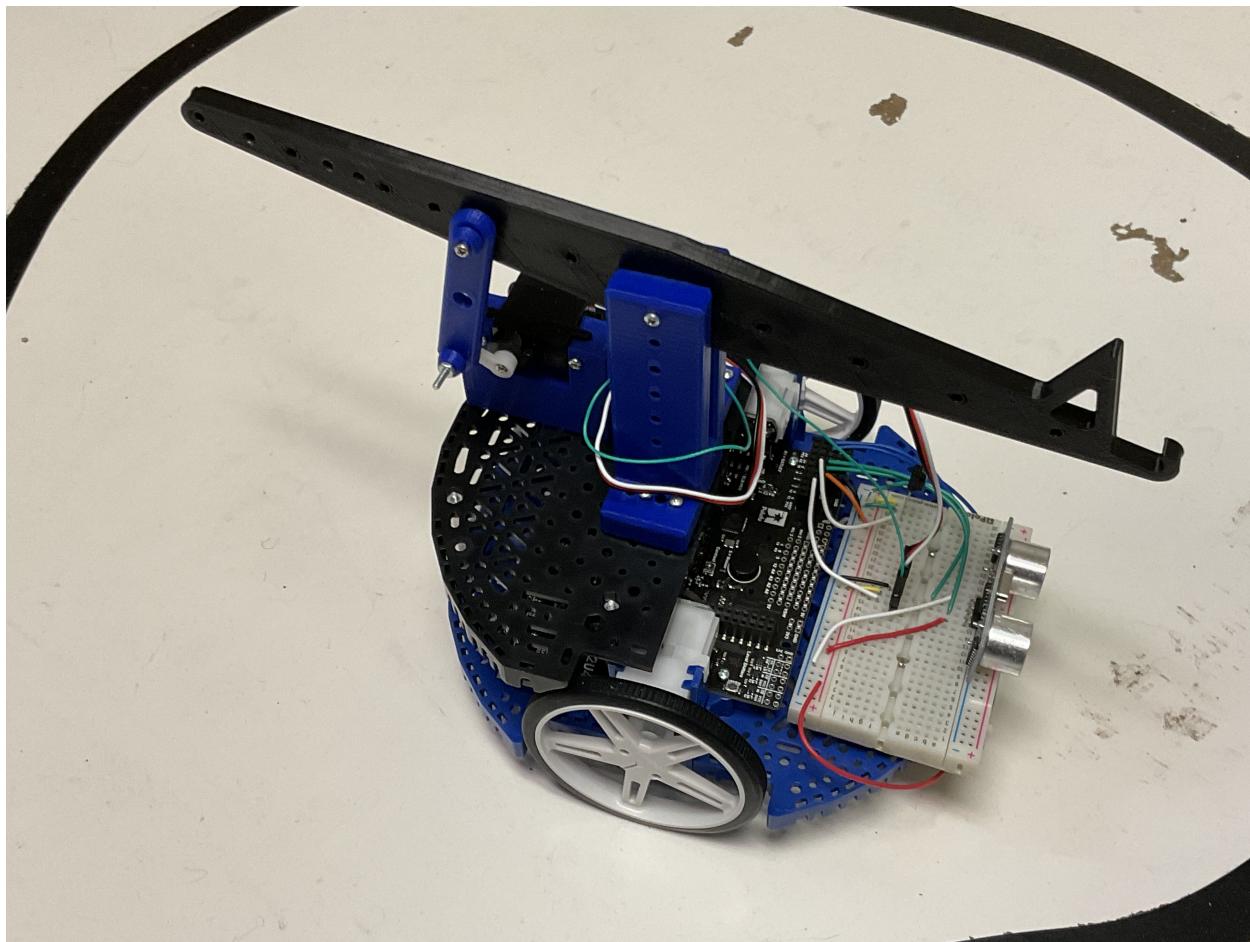


Figure 10: Romi built and wired.

Figure 11 shows an annotated version of [the control board](#).

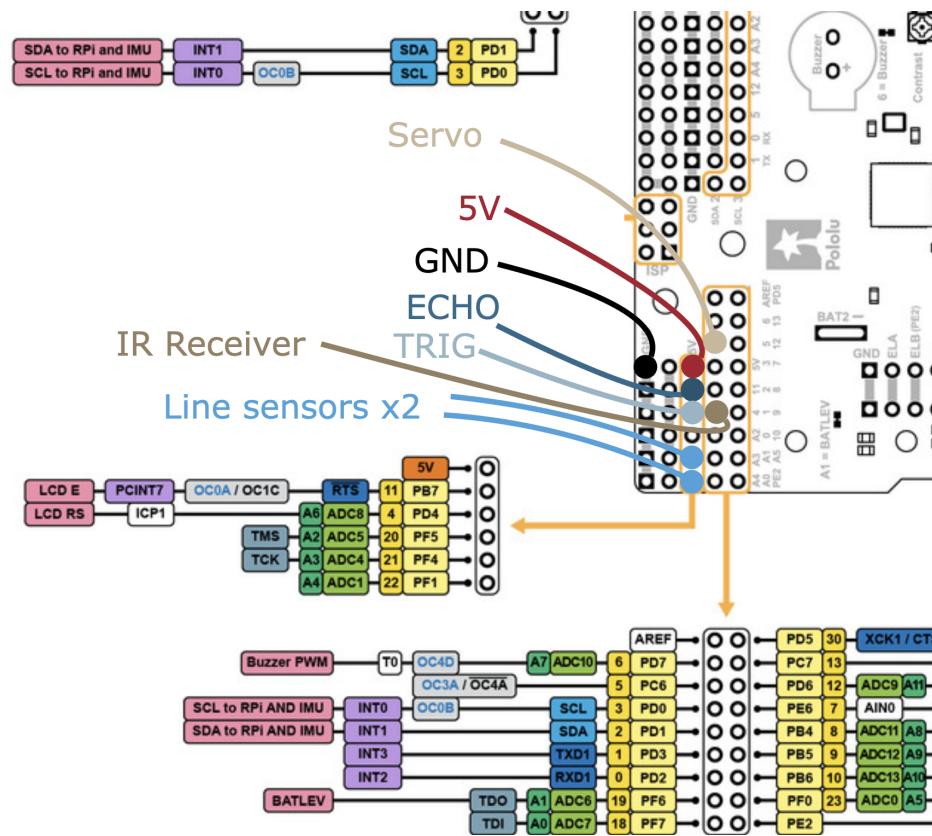


Figure 11: Control board layout with wiring connections annotated. 5V and GND should go to the power rails on your breadboard, and then you can connect power to the various sensors from there. Note that the colors do **not** match the color in Figure 10

3 Appendix

3.1 Bill of Materials

Each robot kit includes the following materials:

Item	Qty.	Link
Romi chassis kit	1	https://www.pololu.com/product/3500
Extra ball caster	1	https://www.pololu.com/product/3539
Expansion plate	1	https://www.pololu.com/product/3560
Encoder pair (pre-soldered to motors)	1	https://www.pololu.com/product/3542
Control board (pre-soldered and mounted)	1	https://www.pololu.com/product/3544
USB cable	1	https://www.pololu.com/product/2073
IR remote	1	https://www.pololu.com/product/2777
IR receiver	1	https://www.pololu.com/product/2471
Micro servo (w/feedback)	1	http://www.pololu.com/product/3436
Reflectance sensor array (pre-soldered)	1	https://www.pololu.com/product/4246
Ultrasonic rangefinder	1	https://www.sparkfun.com/products/15569
Breadboard w/mounting holes	1	https://www.pololu.com/product/4000
Breadboard wire kit	1	https://www.pololu.com/product/312
Breakaway pin headers	1	https://www.pololu.com/product/1065
3/4" standoffs	2	https://www.pololu.com/product/1943
1" standoffs	2	https://www.pololu.com/product/1944
1 1/2" standoffs	2	https://www.pololu.com/product/2009
plastic tubing	1-2"	Cut to use for spacers
2-56 nuts	20	https://www.mcmaster.com/91841A003/
1/4" 2-56 screws	10	https://www.mcmaster.com/91772A077/
3/4" 2-56 screws	10	https://www.mcmaster.com/91772A084/
1 1/4" 2-56 screws	3-4	https://www.mcmaster.com/91772A266/
Arm assembly	1	See Figure 2
AA batteries	18	-

Table 1: Bill of Materials

Also included in each kit, but not used are:

Item	Qty.	Notes
3/8" standoffs	3-4	Included with chassis kit, but wrong thread (M2.5)
Mounting bracket for rangefinder	1	Included with arm assembly, but not needed

Table 2: Extra parts that aren't used.