

One week after League 1 and we spent most of the meeting reflecting on what happened during League 1 and what we could do better. We also talked with Ramesh uncle on some strategies for League 2. We also had a discussion about ways to stop from moving more than five pieces of debris at a time and whether that rule applied to autonomous.

The robot has had some great input. The ramp was replaced and the climber release systems were tested. Plexiglas was added with warning signs. The robot didn't go through many major changes, except for the power distribution module. The new power distribution module that was put in affected us during league. This was how our robot evolved from league 1 to league 2.

League 2 was a HUGE learning experience for our team. During this league we were only able to run one full match with a fully functioning robot. Why? It was losing connection from the phone and the Core Power Distribution Model. After this league, how team had one set goal: to create a system that would keep the USB tight and in place. We looked at different 3D Printing Options, but none of them were right for our team. We tried using different zip tie arrangements and foam cushioning. None of these individual tactics ever worked. So what do we end up doing? We combined all these different strategies to create a stable and secure USB. This was, putting the phone on a sponge.

Since league 3 we have changed multiple things. During this time we added a carrier for the climbers to use during autonomous and extended the climber releaser. We tried making another climber release but we removed it later on, realizing that it wouldn't work with the design of our robot. Other than that we just fixed the place glass and added labels to the robot.

