Notes:

MechE:
(Harvard)
- Evelyn Park
- Kate Donahue
- Miesha (??)
(MIT)
- Aaron Ramirez
- Ryan Fish
- Baker Logan
- Jonathan Hechtbauer
- Elizabeth Scheanne
- Oscar Viquez-Rojas
- Jaguar Kristeller

CS:
(Harvard)
- Svilen Kanev
- Jessica Yao
(MIT)
- Benjamin Tidor
- Matthew Arbesfeld
- Benjamin Reynolds
- Sheena Nie
- Caroline Morganti
- Adam M Gleitman
- Nicolas Bravo
- Jaguar Kristeller
- Katie Bartel
- Ben Mattison

EE:
- Lisa Liu
- Rui Jin
- David Kaufman
- David Gaddy
- Sheena Nie
- Markus Webert
- Manny Singh
- Anna Walsh
- Erwin Hilton

Computer science

- starting to assign project in simulation

MechE:
- hard to keep people busy b/c so many people
- one new guys wants to redesign kicking setup
-- hard to do, but letting him do it
- Kate ended up reading a lot of the relevant papers
-- data gathered on, benchmark in relation to other teams? e.g. top speed, top kicking velocity
    - top teams got 10 m/s
    - we're at 1.5 m/s
- robot speed, kicking speed

EE:
- debugging
- dribbler - interface with MechE
- kicker - interface with MechE
-- variable kicking speed

How do you measure kicking speed?
A: how long it takes for the ball to get across the field, and also launch ball off end of table and see where it ends
Alternative: using a camera might be difficult
Solution: need acceleration, lower center of mass (motors)
Single board design, removing the vertical boards? Weight them to quantify it.

Budget:
- we're getting money from Harvard
-- background: they moved to new funding structure, where we had to apply... aaaand we got it! We get $4000. (HCES got $4000) next year we will probably get all the funding ourselves.

-- motors ($65/each) -- Oscar can buy things
-- projector or big screen - lisa will look up projectors;
-- storage racks/bins for organizing things - Aaron will look this up

Spoke to Radhika about class, soonest is next fall
-- wasn't completely happy, wanted to buy robots off shelf to teach using those
-- if we can demonstrate in Spring if our robots are reliable, we can run the class with her
-- or we can make it relevant to robocup as a simulations based class

SSL Survey
- strive for maximum possible ball speed, and then lower

MechE - move battery packs to back; balacnes out the stuff in the front; change orientaiton of battery packs;
Q: Will kicker get in the way?
A: Can get redesigned.

MechE

All team meeting
- check what next round of exams are (end Nov?)
- try to show a 2 vs 2 game (4 working robots)
- get food in Harvard Square

Chipper

- Solenoid model numbers:
Magnetic Sensor Systems
S-15-75
http://www.magneticsensorsystems.com/solenoid/tubular/s-15-75.asp
S-20-100
http://www.magneticsensorsystems.com/solenoid/tubular/s-20-100.asp

- standalone kicker board
    - press a button to make it kick
- take a look at losses in the solenoid

Q: can we vary the kicking power
A: capacitors charge up to 250 V, in 10V increments; not sure how it maps to ball speed; tried to look at it before, but very noisy
relevance: for chip kicking

Svilen: A lot of noise was due to ball positioning due to center of kicking
Aaron: If we can tighten up dribbler to keep ball centered

Breakbeam