

Thanks for coming to the meeting today. For those of you who couldn't make it, here are some points from today's meeting:

Think about small projects you want to do to improve the robot

- Suggestions: measuring kicking speed / distribution, optimizing efficiency of energy transfer from capacitors to ball, multiple kickers / chip kicking, optimizing dribbler, optimizing break beam, characterizing robot acceleration

- Work in groups if you want

- Think about small projects you want to do to improve the robot
 - Suggestions: measuring kicking speed / distribution, optimizing efficiency of energy transfer from capacitors to ball, multiple kickers / chip kicking, optimizing dribbler, optimizing break beam, characterizing robot acceleration
 - Work in groups if you want
- Auxiliary kicker and kicker boards form a subsystem on the robot for charging up the capacitors and kicking the ball
- Auxiliary kicker board communicates with off board computers
 - Tells kicker board to charge capacitors / kick ball
 - Tells dribbler to turn on/off
- Kicker board controls charging the kicking capacitors and kicking the ball
 - Charge the capacitors by storing energy in transformer and dumping onto capacitor
 - Kick the ball by dumping energy from capacitors into solenoid
- MOSFETs are switches used to turn on/off current
 - MOSFETs have 3 terminals: gate, drain, source
 - Raise voltage at gate to turn on switch between drain and source\

Lower voltage at gate to turn off switch

Please do the Eagle tutorial! I've attached the tutorial again in this email. If you still don't have access to the Robocup EE files on Git, I'll show you next meeting.

Next week is a 4-day weekend, and we'll send out a Doodle to see what times people are available. We'll be talking about the brushless boards.