Ruffin White

Spencer Carver

ME435

Project Plan

We plan using an industrial dustpan to scoop the balls from the ground. The tip of the dustpan is adjusted so that it contacts the tee just under the ball, which will cause the ball to roll into the pan over a small lip (has worked in manual tests). The dustpan will be mounted to the front of the robot using the bolts.

The balls will be guided to the center of the dustpan where they will fall into the occupancy sensor, which will be recessed in the surface of the pan.

The arm will then reach down, pick up the ball from the sensor, and move it back to the golf ball stand, where it will be analyzed, and either discarded over the side, or kept. If a ball is kept, the robot chooses the next position for the next ball to be analyzed.

