Overall Priority (1=high)	Are we done yet?	Assigned TO??	Req #	Priority	Difficulty	Math = Prio * Diff	Drive Requirement Descriptions	Date Started	Date Finished
0	100		DR 01	1	1	1	**Drive:** There will be four independent Mecanum wheels.	1/20	1/23
0	100		DR 02	1	1	1	**Drive: R**obot will drive forward and reverse	1/20	1/23
5	50	ML, AR	DR 03	1	1	1	**Drive: R**obot will "strafe"		
0	100		DR 04	1	1	1	**Drive:** Robot will be able to make turns to the left or right.	1/20	1/23
0	100		DR 05	1	1	1	**Drive:** Robot will stop moving when driver controls not engaged	1/20	1/23
0	100		DR 06	2	3	6	**Drive:** A Gyro chip is to be added to the robot.	1/28	1/28
5	0		DR 07	3	3	9	**Drive:** An Accelerometer chip is to be added to the robot.		
3	0		MR 01	1	1	1	**Minibot-Release: MOST LIKELY SERVO**		
1	0		MR 02	1	1	1	**Elevator:** Will have two motors that act together. **2-Window Motors avail NOW**		
2	0		MR 03	2	2	4	**Elevator:** At the extreme ends of the elevator, use limit switches (poss just encoders)		
1	0		MR 04	1	1	1	**Elevator:** Manual control of the elevator to go up or down		
2	75	MP	MR 05	1	2	2	**Elevator:** Encoder is necessary on the Elevator - 'height'.	1/29	
1	0		MR 06	1	1	1	**Arm:** Will be controlled by one motor. **1-Banebot 550 motor and trans avail NOW**		
2	25	AS	MR 07	1	2	2	**Arm:** An Encoder is needed to assist with measuring angle	1/29	
2	0		MR 08	2	2	4	**Arm:** The Arm will rotate within the range of two extremes (poss use JUST encoders)		
2	0		MR 09	1	2	2	**Arm / Elevator Combos:** the **Inspection** position		
3	0		MR 10	2	2	4	**Arm / Elevator Combos:** eight preset positions.		
4	0		MR 11	1	2	2	**Claw:** Two rollers controlled by two motors		
4	0		MR 12	3	1	3	**Claw:** Catch-AutoStop: Add limit switch at back of claw		
0	100	JL	KR 01	2	1	2	**Camera:** Streaming: output to Classmate in Driver Station.	1/29	1/31

4	0		KR 02	3	3	9	**Camera:** The Camera's "default" position (viewing wise)		
4	0		KR 03	3	3	9	**Camera:** TILT 45 degrees up/down on Y-axis.		
4	0		KR 04	3	2	6	**Camera:** PAN 45 degrees left/right on X-axis.		
0	100		DC 01	1	1	1	**Driver Control:** Button-11 Robot to go in straight line	1/20	1/23
0	100		DC 02	1	1	1	**Driver Control:** Button-12 Robot to change orientation	1/20	1/23
3	0		DC 03	3	1	3	**Driver Control:** Button-5 or Button-6 – 50%/75% speed reduct		
1	75	MP	DC 04	1	1	1	**Driver Control:** Button-8: Disable Gyro while button pressed.	1/29	
3	0		OC 01	3	1	3	**Operator Control:** Button-11 (left hand joystick): Pan/Tilt cam.		
3	0		OC 02	3	2	6	**Operator Control:** Button-11-PRESSED - Camera – 'default' pos		
1	0		OC 03	1	1	1	**Operator Control:** Button-5: Arm Rotation - UP		
1	0		OC 04	1	1	1	**Operator Control:** Button-7: Arm Rotation - DOWN		
1	0		OC 05	1	1	1	**Operator Control:** Button-6: Elevator Movement - UP		
1	0		OC 06	1	1	1	**Operator Control:** Button-8: Elevator Movement – DOWN		
1	0		OC 07	1	1	1	**Operator Control:** Button-1: Claw – Catch Tube		
1	0		OC 08	1	1	1	**Operator Control:** Button-2: Claw – Roll Tube Down		
1	0		OC 09	1	1	1	**Operator Control:** Button-3: Claw – Release Tube		
1	0		OC 10	1	1	1	**Operator Control:** Button-4: Claw – Roll Tube Up		
2	0		OC 11	2	1	2	**Operator Control:** Button-9: Camera Streaming On/Off		
2	0		BC 01	1	1	1	**Switch**: Minibot / Endgame – switch to deploy the Minibot.		
3	0		BC 02	3	2	6	**Indicator**: (Minibot):		
3	0		BC 03	3	1	3	**Indicator**: (Line Sensors):		
1	0		BC 04	1	1	1	**Switch**: Autonomous – Line Selector (3-position-switch)		
1	0		BC 05	1	1	1	**Switch**: Autonomous – Grid Height Selector (3-position-switch)		
2	0		BC 06	2	1	2	**Buttons**: Scoring Grid Presets (6 of them)		
3	0		BC 07	2	1	2	**Button**: Ground Catch		
3	0		BC 08	2	1	2	**Button**: Feeder Slot		

4	0		BC 09	3	1	3	**Button:** Feeder Slot Request Button			
4	0		BC 10	3	1	3	**Indicator:** Feeder Slot Request Beacon			
3	0		BC 11	3	1	3	**Indicator: Claw Catch Indicator:** An LED will illuminate when the			
1	0		BC 12	2	1	2	**Classmate: Camera Streaming Output:** Stream output from t			
2	0		AR 01	1	2	2	Initialize Encoders (Drive, Elevator and Arm), and Gyro prior			
1	25	MP, ML	AR 02	1	1	1	Robot will operate for the full 15 seconds	1/29		
2	0		AR 03	1	2	2	Robot shall determine Scoring Column and Scoring Peg to target			
1	50	MP, ML	AR 04	1	2	2	Using Light Sensors (and Encoders if its warranted),	1/29		
2	0		AR 05	1	2	2	Move Elevator/Arm into Scoring position from Pre-Auto position			
2	0		AR 06	1	2	2	Move Elevator and Arm based auto switches (all 6)			
3	0		AR 07	1	2	2	Place Ubertube on Scoring Peg.			
5	0		AR 08	3	3	9	Use Camera for targeting the Scoring Pegs			
5	0	AS	TR 01	1	2	2	"Zero Out" Integral portion of the PID algorithm.			
5	0		MH 01	3	3	9	Driver Station Requirements for OTHER team:			
5	0		MH 02	3	3	9	Robot Requirements of the OTHER team:			
5	0		MH 03	3	3	9	Programming Requirements of the OTHER team:			
5	0		MH 04	3	3	9	Mechanism Requirement of the OTHER team:			