

The distance sensor: Due to the AWP program, we need to let the Robot contact with the elevation bar. To ensure the Robot that enters the channel correctly. The Robot tends to veer to the right while moving. To ensure that the distance sensor detects the bar without crossing the line, we repositioned the distance sensor to the left side.

⊙ Elevation

During today's training, we discovered that the side-elevating mechanism was not stable. Whenever the Robot climbed onto the bar, the front of Robot would tilt downward, increasing the chance of touching the ground.

Additionally, due to the hard flex wheels not being able to to make contact with the barrier pole, making it even more challenging to adjust a balance position.

After a group discussion, we notice the issue might be related to the Robot center of gravity. So we add a bearing bracket at the empennage. This allow the Robot's chassis with rubber wheels to touch the bar, ensuring the stability.



project

V5

designed by:

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date:

6.2.3