However. during the debugging process, we found that the Triballs couldn't even touch the rubber band. As a result, we added a 1x1 L-shaped beam on top of the two nut columns to secure the position of Triballs.

Furthermore. we discovered that the intended hitting point for the Triballs was not where we intially thought. It was actually in the middle section of the cata-arm. after further adjustments, we placed a rubber mushroom head at the rear of the Robot. which was finally determined as the hitting point.

In subsequent cata attemps, the throwing distance was still not far enough. Therefore, we ultimately decided to replace the motor with a larger one and use a 1:2 gea ratio along with a 100RPM gearbox. At the same time, we added a 24T counterweight gear on the cata-arm to increase the impact force during the moment of collision.
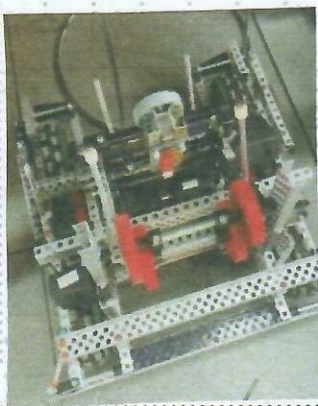
Finally, we repeatedly adjusted the hitting point of the Triballs for better accuracy. We also tried using a rubber wheel for throwing, but we latter found that it lacked precision.

project VJ. cata   designed by: Kevin   witnessed by: Steven
                                                                    date: 1. 10