

the intake mechanism was unable to lift properly. After investigation, we found that the intake rope restricted the maximum lifting point of the intake mechanism. Initially, we wanted the Robot's elevation arm to lift the Robot in case of a flip, but based on the performance in the training, the rope severely affected the Triball intake into the frame. Therefore, we have decided to remove the rope tomorrow and abandon the self-rescue function of elevation arm.

Fourthly, there was an issue with the ratchet. After completing the elevation, the Robot failed to lock properly. Upon inspection, we found that the nut on ratchet was loose, causing the screw to slip and not engage with the gear. It is also possible that the screws were too long. Tomorrow, we plan to try shortening the screws slightly to address this problem.

Lastly, there was a problem with the distance sensor. During the left autonomous part, the Robot failed to stop using distance sensor. After the match, we discovered that the indicator light on the sensor was on. We believe that there might be an issue with the port settings in the program or the placement angle of the sensor. We hope to resolve this issue tomorrow.

project

designed by:

witnessed by:

date: