Post FLR Action Plan

Drivetrain

- Remove axle collars
- Replace axle collars with split spacers
- Chamfer the 9T sprockets
- Add spacers under both drive pulleys (18T & 56T)

Arm

- Replace belt drive with helical gear drive
- Replace 360° encoder with lower span potentiometer or encoder
- Tuning

Claw

- How to convert to roller claw?
- Can we drive from elbow?
- Do we still need wrist?
- One motor or two?

Minibot

- Flip the cylinder to deploy backwards
- Design / form / install Hanger for Minibot
- Mount camera to facilitate accurate deployment
- Resolve camera com issues
- Set specification around minibot function/features
- Design & build new minibot(s)
- Obtain and document statistical data on minibot performance
- Order more motors
- Interchangeable deployment plates
- Satisfied with deployment x-above points

Software

- Get outboard autonomous deployment working - with "pointy spikes" in mind
- Get straight-line autonomous deployment working reliably
- Obtain and document statistical data on autonomous performance
- Integrate the drive team into software development and testing (need to facilitate this process)
- Low priority: "Y" Center-Line following and scoring

Drivers' Station

- Document Control System (what button does what?)
- Move laptop screen to driver's side

Process

- Update list of spare parts, tools & other take-along items based on FLR experience
- Battery Caddy (Kellom)
- Test and clearly label all batteries
- Develop and document battery deployment plan
- Update the pit checklist
- Update the field checklist
- Post-match meetings

Field Mods

- Use diamond-plate as the target for autonomous wall
- Cover bottom of tower
- Weight or anchor tower to prevent tower movement when deploying

Driver Practice

- Driver & Operator need to practice their own jobs as a team (no 2nd team or cross-training until after Championship) with a coach
- Get DB6 (& DB3 if practical) running as op-for robots (and driver training)
- Play loud music