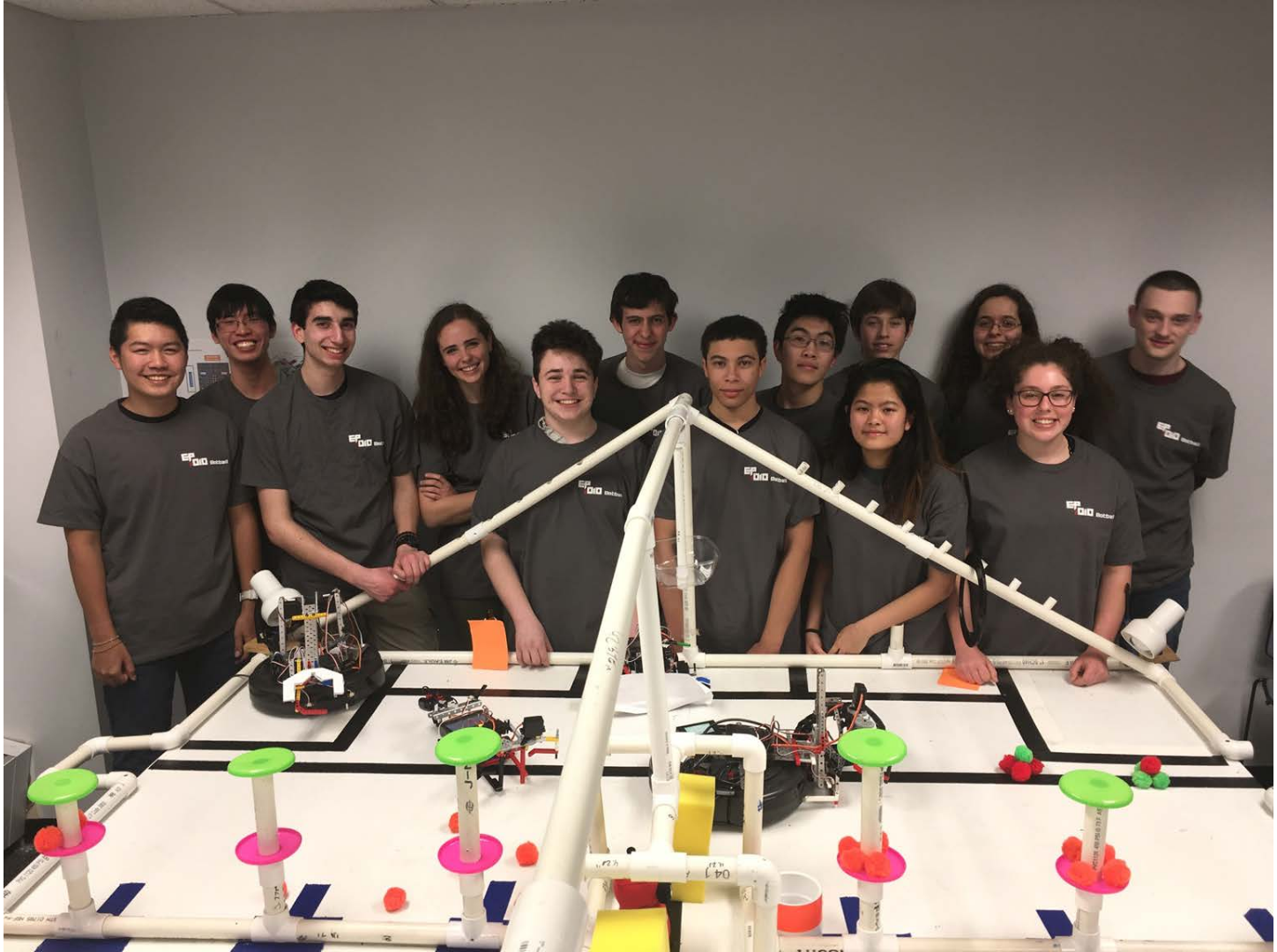
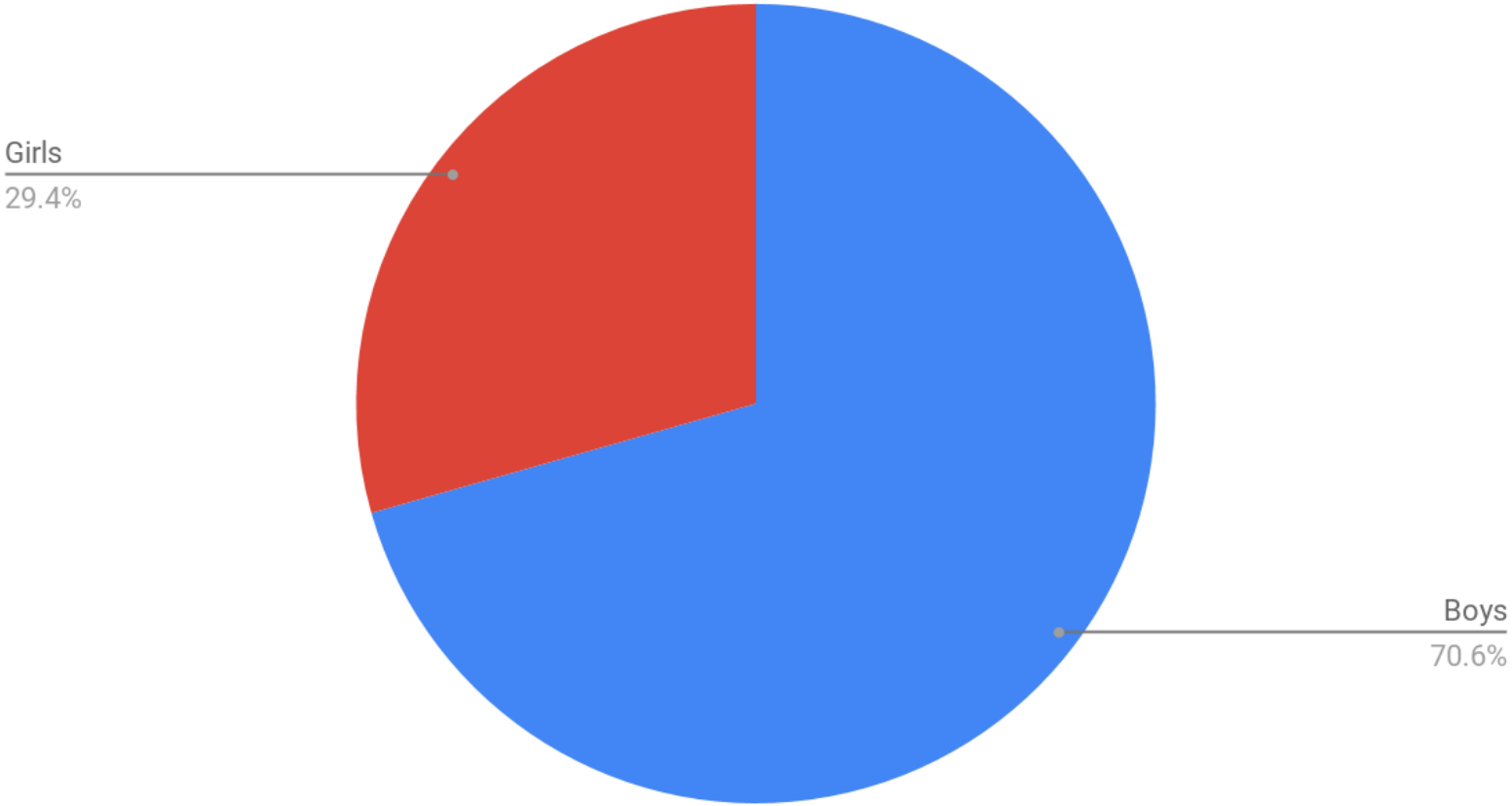
Explorer Post 1010

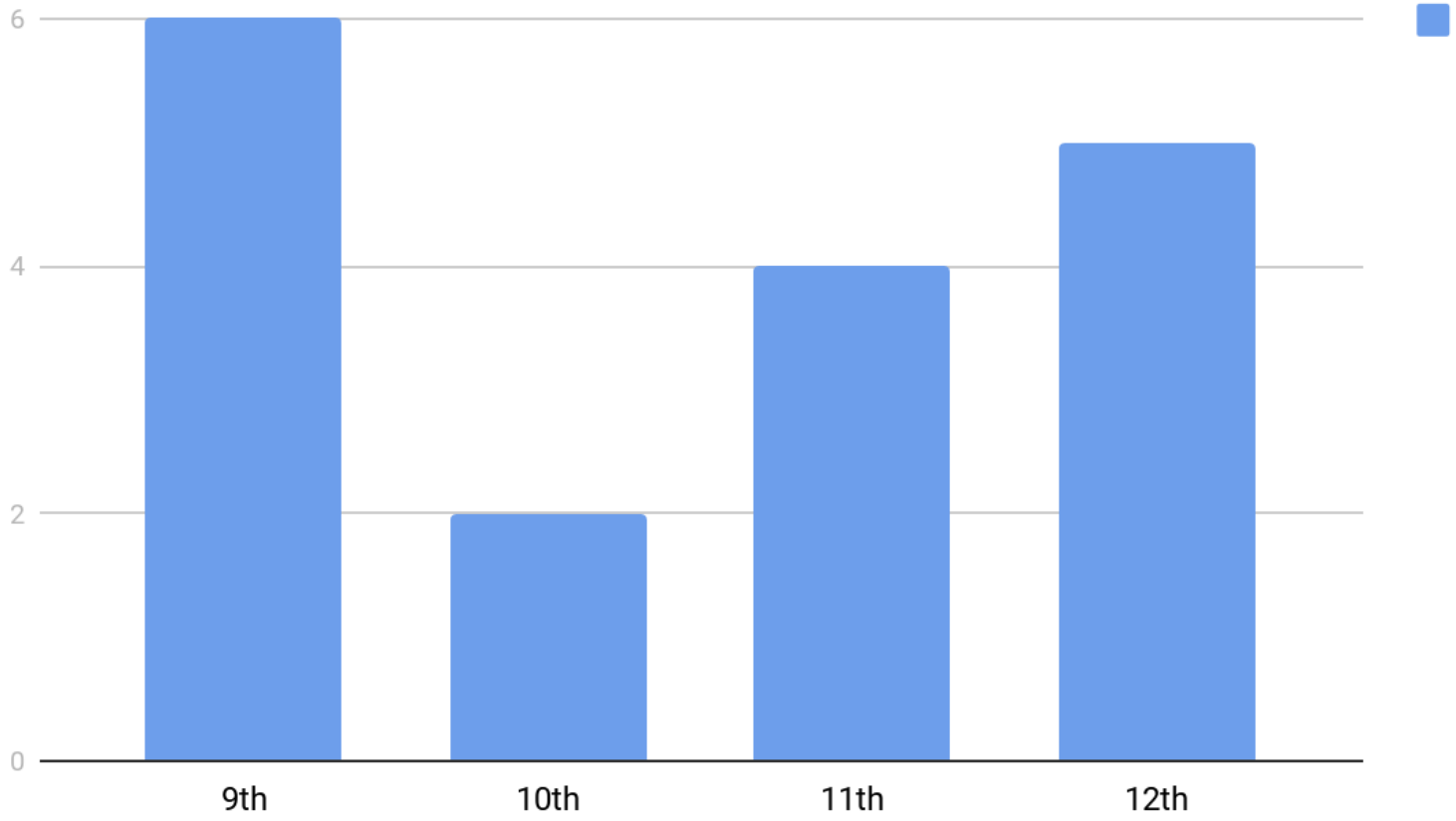
Jacob Barats, Kristina Znam

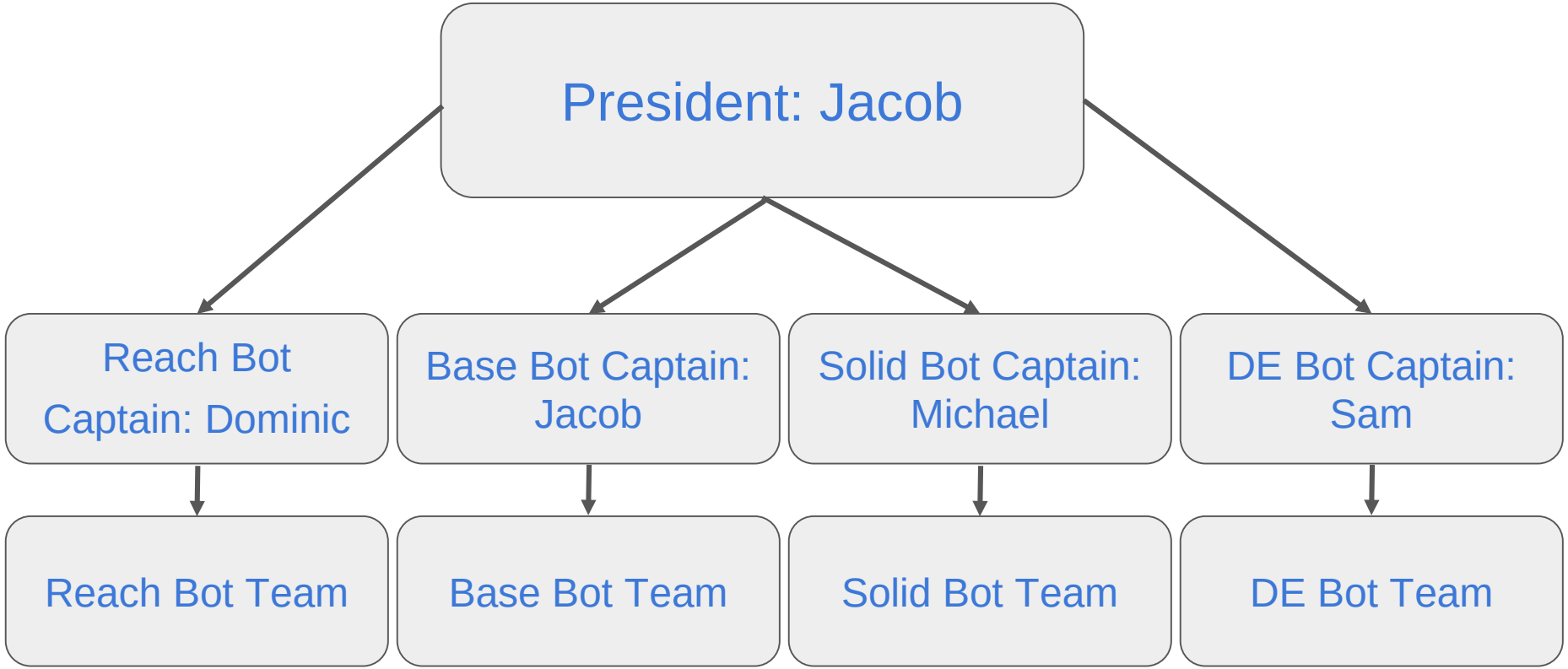


Gender Split



Student Grade Levels




President: Jacob
Reach Bot Captain: Dominic
Base Bot Captain: Jacob
Solid Bot Captain: Michael
DE Bot Captain: Sam
Reach Bot Team
Base Bot Team
Solid Bot Team
DE Bot Team

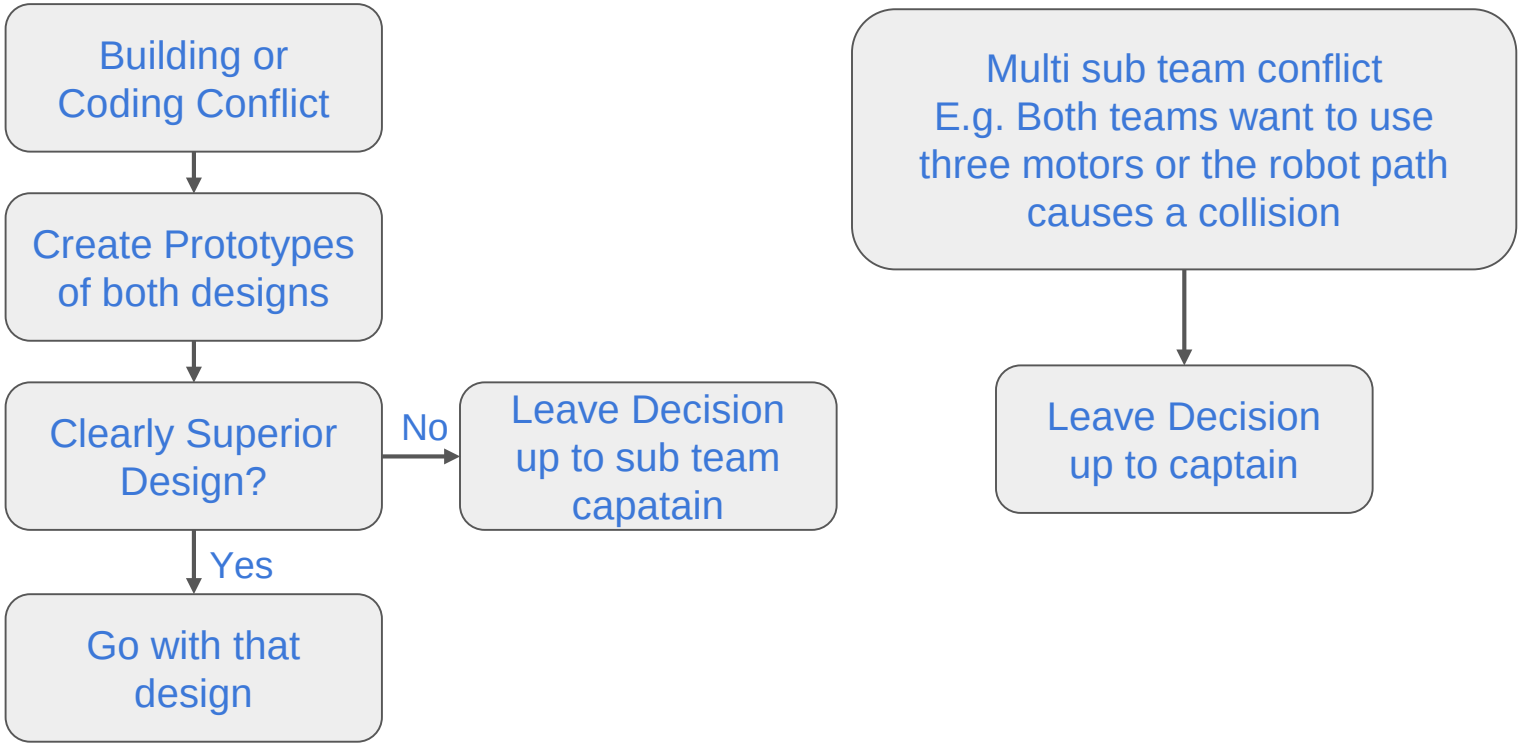
Meetings

Location: Johns Hopkins, 9601 Medical Center Drive

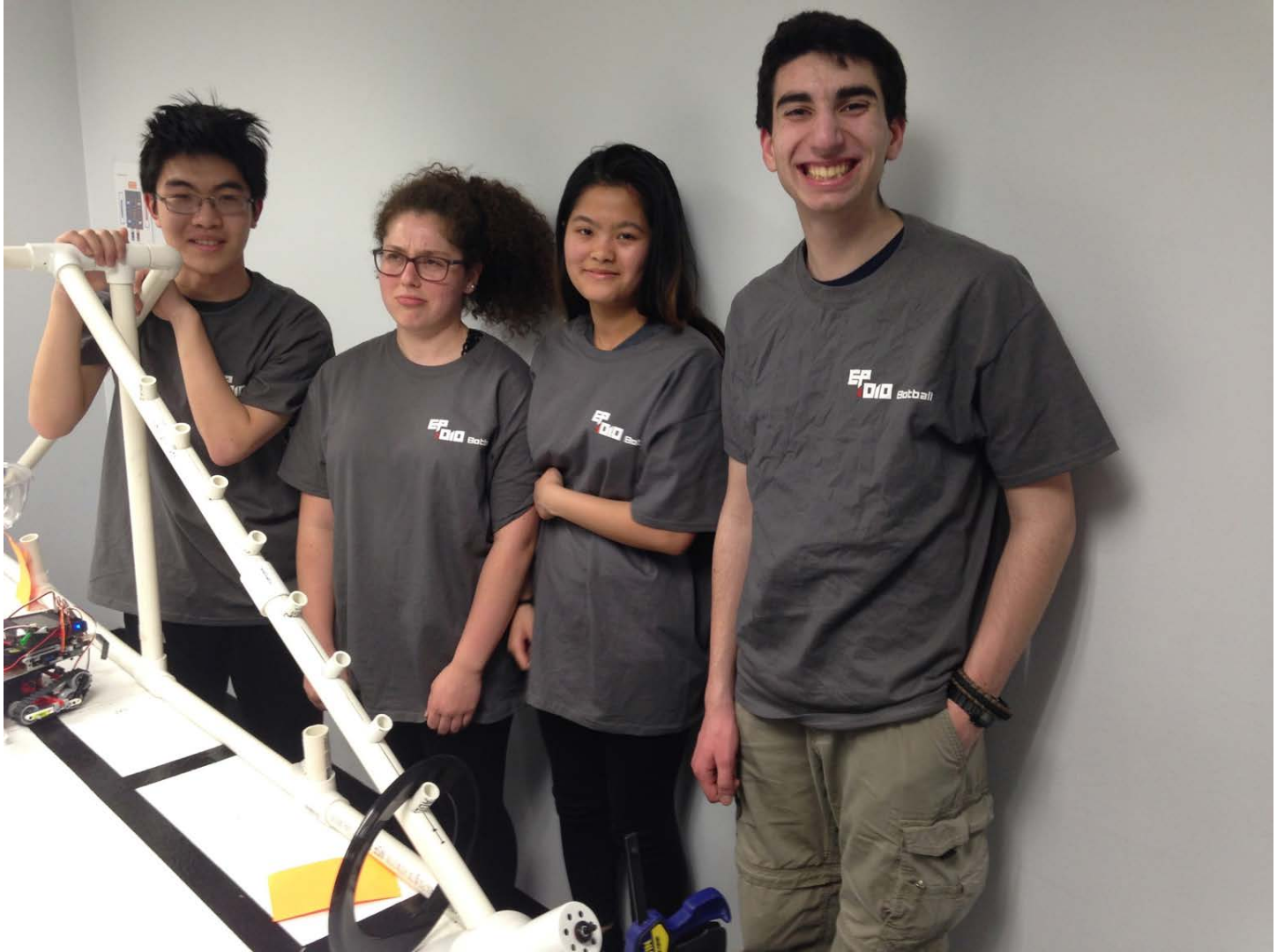
Non School Based Team

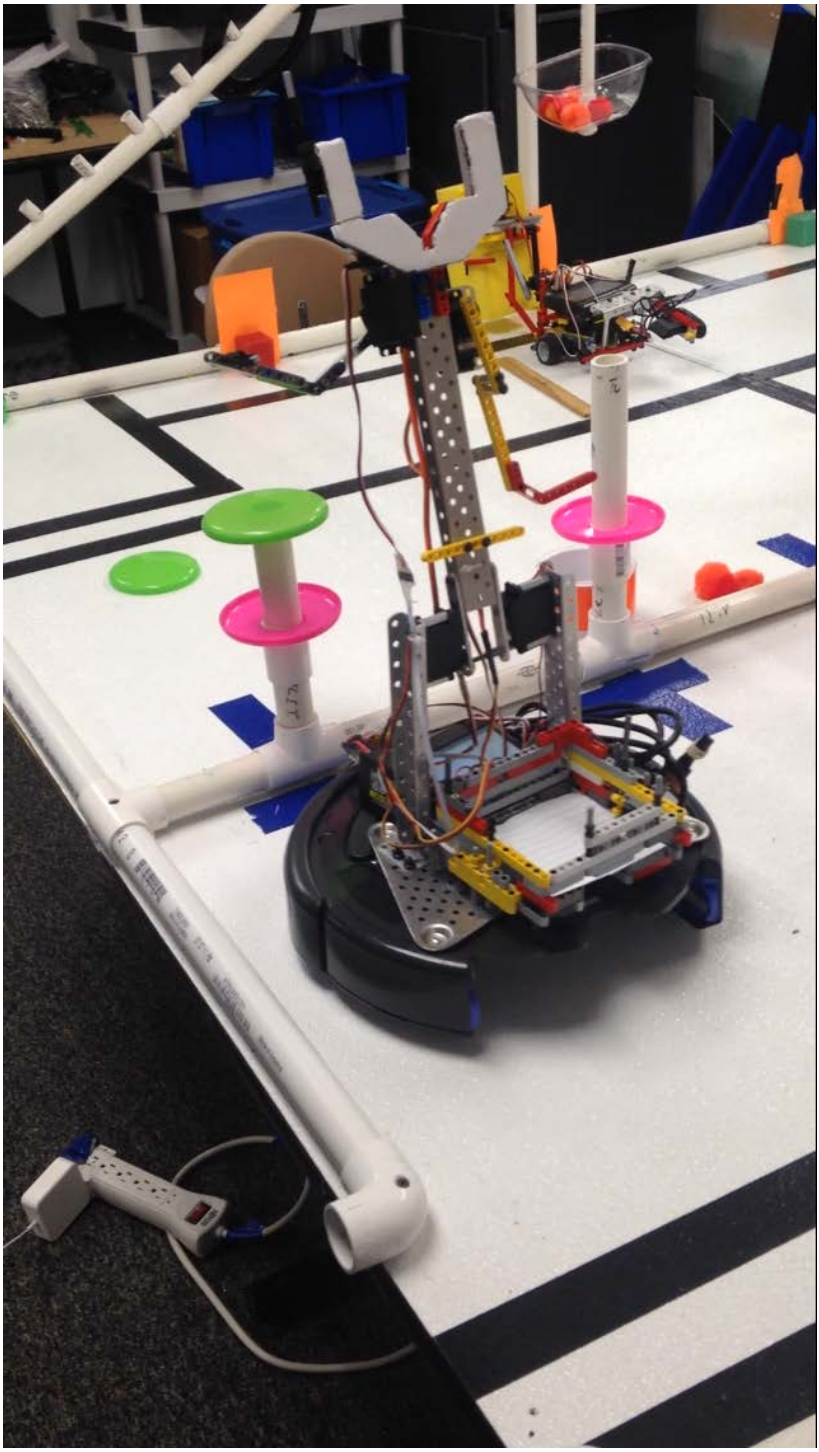
Monday	Tuesday	Wednesday	Thursday	Friday	Saturday	Sunday
6pm-9pm		6pm-9pm			10am-5pm	

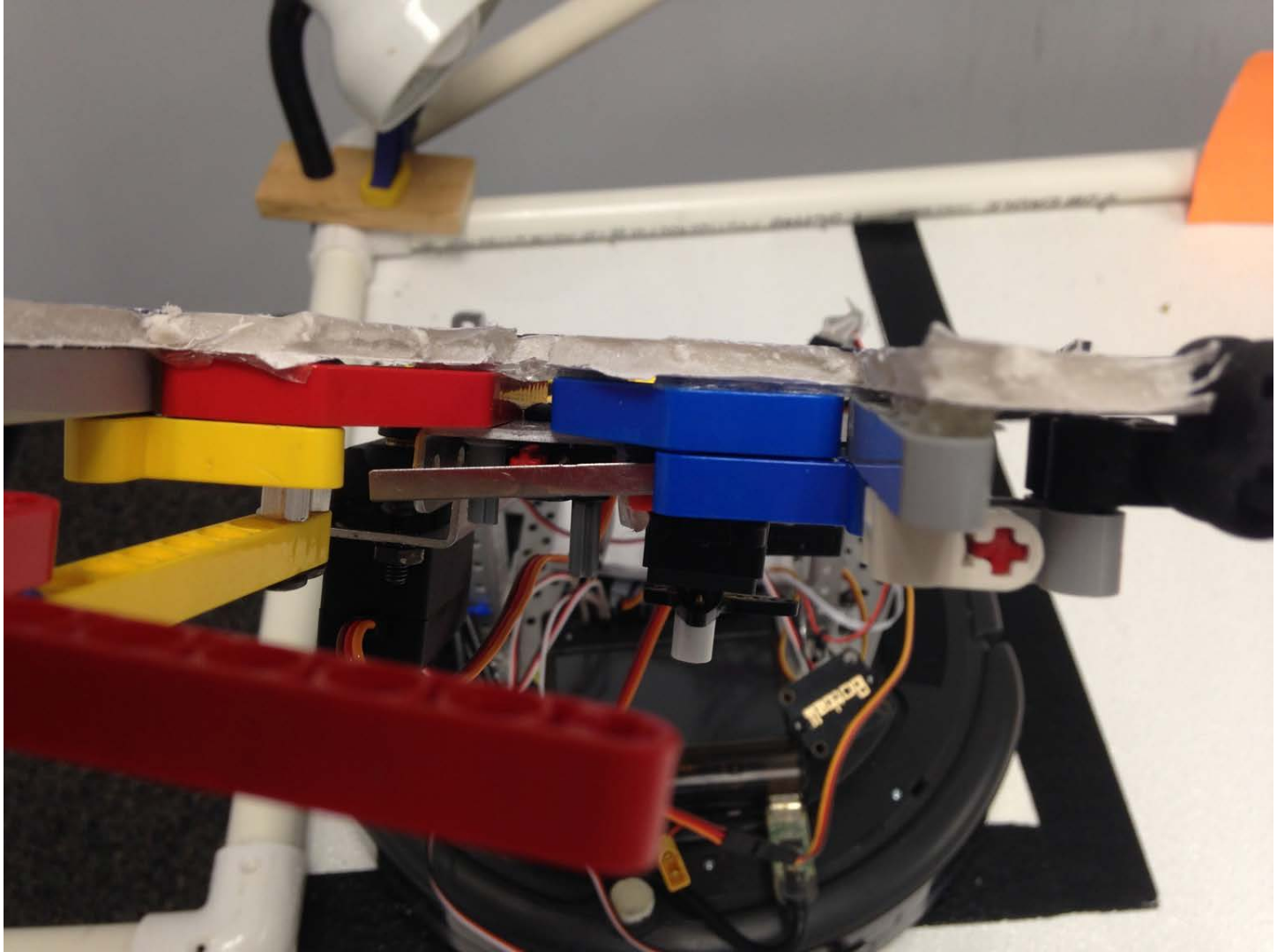
Conflict Resolution



Reach Bot





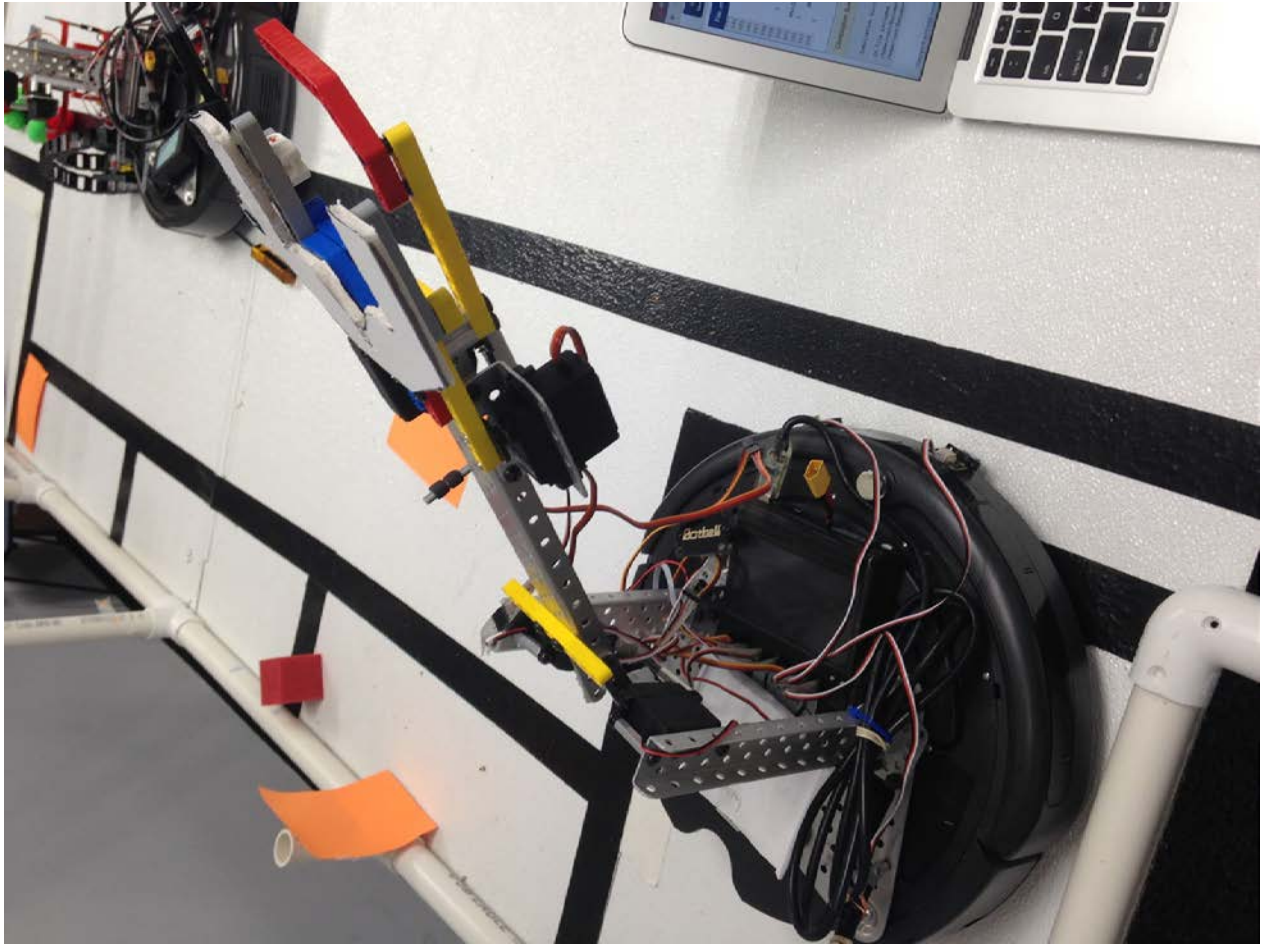


Touch Sensor

- On end of claw to navigate to frisbees

Double Motor Arm

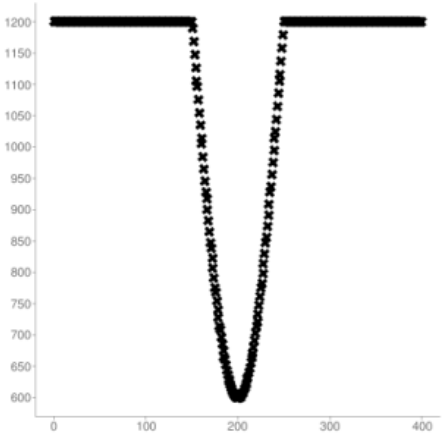
- Capable of lifting the heavy metal arm
- Coding incorporates ticks to move to specific positions



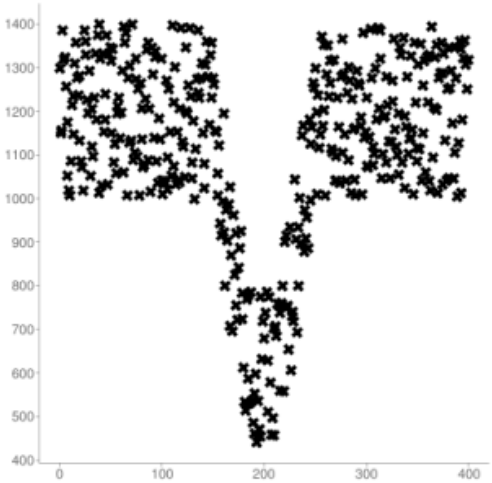
```
int wl=analog(LTOP); //Records what the value for white is using a top hat
while(analog(LTOP)<(wl+300)) //The condition is true until the left top hat has a
{                                                                    //spike of 300, indicating the blue line

    create_drive_direct(300,-300); //While the condition is true, turns clockwise by moving the
                                                                    //wheels in opposite directions
}

create_drive_direct(-300,-300); //Create drives straight back for two seconds
msleep(2000);
armMiddle(); //Arm goes to middle position

while(!(digital(button))) //Condition is true as long as the button sensor is not pressed
{
    create_drive_direct(100,100); //Create drives forward
}
armUp(); //Arm raises, catching the frisbee
```

Problem and Elegant Solution

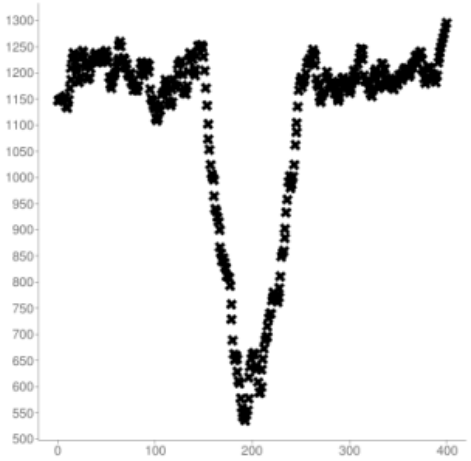
Ideal Depth Sensor passin pipe



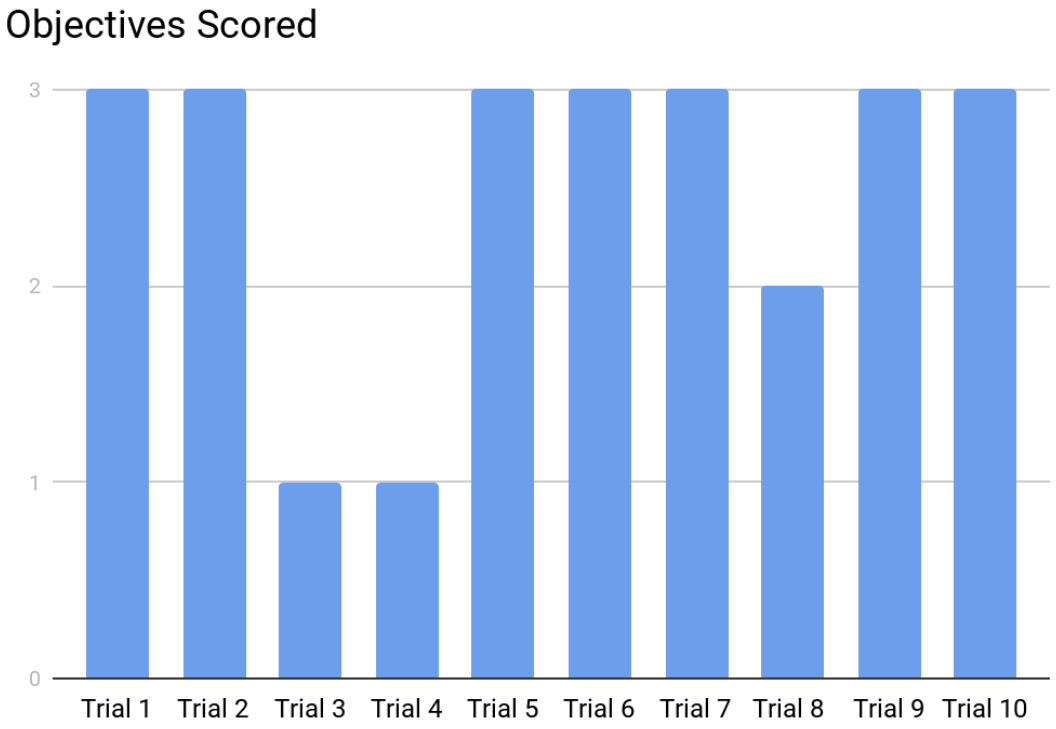
Reality Depth Sensor Passing Pipe



Same Data post radial bias function



Consistency testing



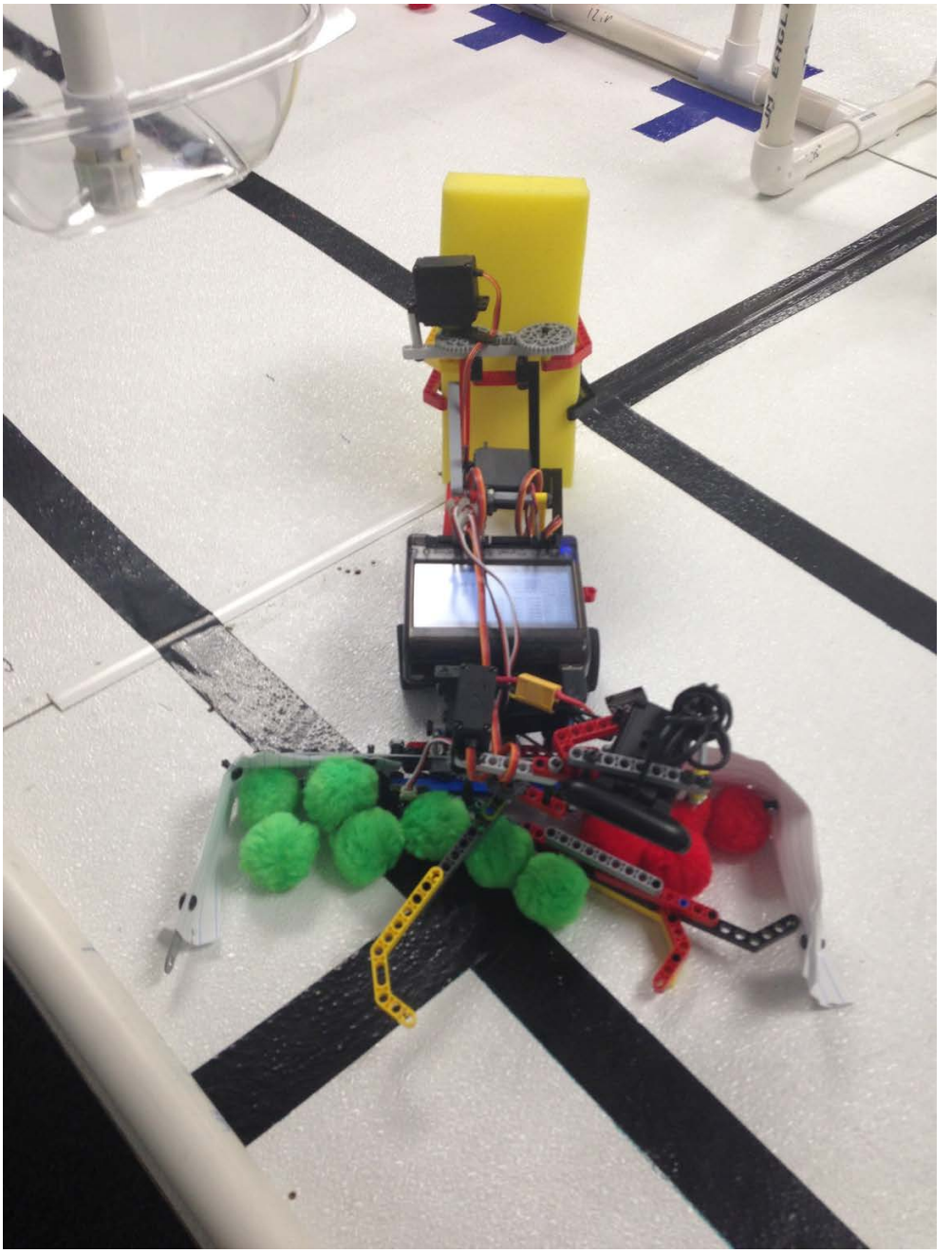
Objective:

- Botguy
- Frisbee
- Tram, position 3

Mean	Median	Mode
2.5	3	2

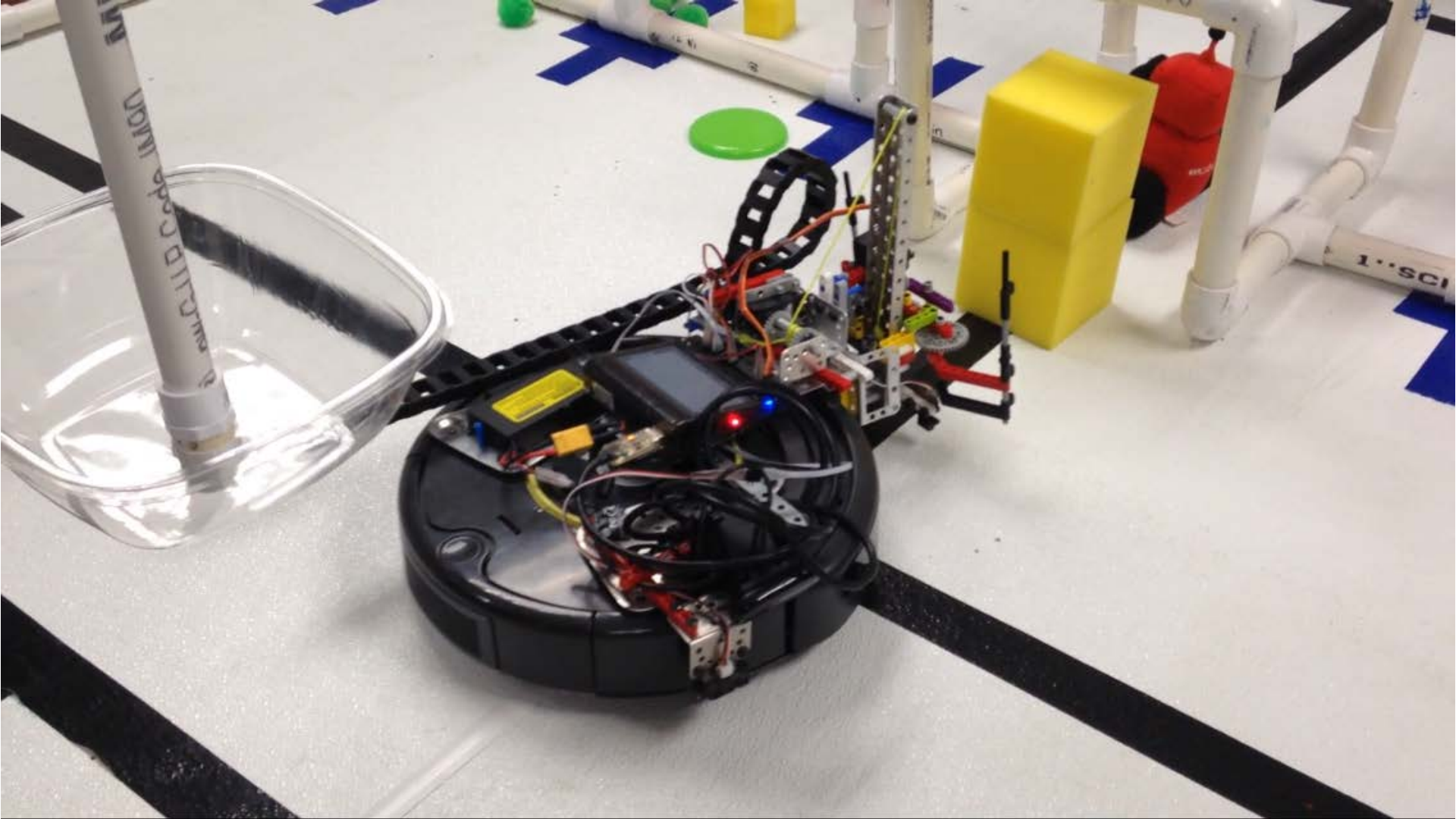
Base Bot


Do Not Erase
Current Rankings
Meetings Competition
OVERALL TEAM RANKING
code change



Solid Bot


Botball



DE Bot