

| Overall Priority (1=high) | Are we done yet? | Assigned TO??? | Req # | Priority | Difficulty | Math = Prio * Diff | Drive Requirement Descriptions | Date Started | Date Finished |
|---------------------------|------------------|----------------|-------|----------|------------|--------------------|---|--------------|---------------|
| 0 | 100 | | DR 01 | 1 | 1 | 1 | Drive: There will be four independent Mecanum wheels. | 1/20 | 1/23 |
| 0 | 100 | | DR 02 | 1 | 1 | 1 | Drive: Robot will drive forward and reverse | 1/20 | 1/23 |
| 5 | 50 | ML, AR | DR 03 | 1 | 1 | 1 | Drive: Robot will "strafe" | | |
| 0 | 100 | | DR 04 | 1 | 1 | 1 | Drive: Robot will be able to make turns to the left or right. | 1/20 | 1/23 |
| 0 | 100 | | DR 05 | 1 | 1 | 1 | Drive: Robot will stop moving when driver controls not engaged | 1/20 | 1/23 |
| 0 | 100 | | DR 06 | 2 | 3 | 6 | Drive: A Gyro chip is to be added to the robot. | 1/28 | 1/28 |
| 5 | 0 | | DR 07 | 3 | 3 | 9 | Drive: An Accelerometer chip is to be added to the robot. | | |
| 3 | 0 | | MR 01 | 1 | 1 | 1 | Minibot-Release: MOST LIKELY SERVO | | |
| 1 | 0 | | MR 02 | 1 | 1 | 1 | Elevator: Will have two motors that act together. 2-Window Motors avail NOW | | |
| 2 | 0 | | MR 03 | 2 | 2 | 4 | Elevator: At the extreme ends of the elevator, use limit switches (poss just encoders) | | |
| 1 | 0 | | MR 04 | 1 | 1 | 1 | Elevator: Manual control of the elevator to go up or down | | |
| 2 | 75 | MP | MR 05 | 1 | 2 | 2 | Elevator: Encoder is necessary on the Elevator - 'height'. | 1/29 | |
| 1 | 0 | | MR 06 | 1 | 1 | 1 | Arm: Will be controlled by one motor. 1-Banebot 550 motor and trans avail NOW | | |
| 2 | 25 | AS | MR 07 | 1 | 2 | 2 | Arm: An Encoder is needed to assist with measuring angle | 1/29 | |
| 2 | 0 | | MR 08 | 2 | 2 | 4 | Arm: The Arm will rotate within the range of two extremes (poss use JUST encoders) | | |
| 2 | 0 | | MR 09 | 1 | 2 | 2 | Arm / Elevator Combos: the <u>Inspection</u> position | | |
| 3 | 0 | | MR 10 | 2 | 2 | 4 | Arm / Elevator Combos: eight preset positions. | | |
| 4 | 0 | | MR 11 | 1 | 2 | 2 | Claw: Two rollers controlled by two motors | | |
| 4 | 0 | | MR 12 | 3 | 1 | 3 | Claw: Catch-AutoStop: Add limit switch at back of claw | | |
| 0 | 100 | JL | KR 01 | 2 | 1 | 2 | Camera: Streaming: output to Classmate in Driver Station. | 1/29 | 1/31 |

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|---|-----|----|-------|---|---|---|---|------|------|
| 4 | 0 | | KR 02 | 3 | 3 | 9 | Camera: The Camera's "default" position (viewing wise) | | |
| 4 | 0 | | KR 03 | 3 | 3 | 9 | Camera: TILT 45 degrees up/down on Y-axis. | | |
| 4 | 0 | | KR 04 | 3 | 2 | 6 | Camera: PAN 45 degrees left/right on X-axis. | | |
| 0 | 100 | | DC 01 | 1 | 1 | 1 | Driver Control: Button-11 Robot to go in straight line | 1/20 | 1/23 |
| 0 | 100 | | DC 02 | 1 | 1 | 1 | Driver Control: Button-12 Robot to change orientation | 1/20 | 1/23 |
| 3 | 0 | | DC 03 | 3 | 1 | 3 | Driver Control: Button-5 or Button-6 – 50%/75% speed reduct | | |
| 1 | 75 | MP | DC 04 | 1 | 1 | 1 | Driver Control: Button-8: Disable Gyro while button pressed. | 1/29 | |
| 3 | 0 | | OC 01 | 3 | 1 | 3 | Operator Control: Button-11 (left hand joystick): Pan/Tilt cam. | | |
| 3 | 0 | | OC 02 | 3 | 2 | 6 | Operator Control: Button-11-PRESSED - Camera – 'default' pos | | |
| 1 | 0 | | OC 03 | 1 | 1 | 1 | Operator Control: Button-5: Arm Rotation - UP | | |
| 1 | 0 | | OC 04 | 1 | 1 | 1 | Operator Control: Button-7: Arm Rotation - DOWN | | |
| 1 | 0 | | OC 05 | 1 | 1 | 1 | Operator Control: Button-6: Elevator Movement - UP | | |
| 1 | 0 | | OC 06 | 1 | 1 | 1 | Operator Control: Button-8: Elevator Movement – DOWN | | |
| 1 | 0 | | OC 07 | 1 | 1 | 1 | Operator Control: Button-1: Claw – Catch Tube | | |
| 1 | 0 | | OC 08 | 1 | 1 | 1 | Operator Control: Button-2: Claw – Roll Tube Down | | |
| 1 | 0 | | OC 09 | 1 | 1 | 1 | Operator Control: Button-3: Claw – Release Tube | | |
| 1 | 0 | | OC 10 | 1 | 1 | 1 | Operator Control: Button-4: Claw – Roll Tube Up | | |
| 2 | 0 | | OC 11 | 2 | 1 | 2 | Operator Control: Button-9: Camera Streaming On/Off | | |
| 2 | 0 | | BC 01 | 1 | 1 | 1 | Switch: Minibot / Endgame – switch to deploy the Minibot. | | |
| 3 | 0 | | BC 02 | 3 | 2 | 6 | Indicator: (Minibot): | | |
| 3 | 0 | | BC 03 | 3 | 1 | 3 | Indicator: (Line Sensors): | | |
| 1 | 0 | | BC 04 | 1 | 1 | 1 | Switch: Autonomous – Line Selector (3-position-switch) | | |
| 1 | 0 | | BC 05 | 1 | 1 | 1 | Switch: Autonomous – Grid Height Selector (3-position-switch) | | |
| 2 | 0 | | BC 06 | 2 | 1 | 2 | Buttons: Scoring Grid Presets (6 of them) | | |
| 3 | 0 | | BC 07 | 2 | 1 | 2 | Button: Ground Catch | | |
| 3 | 0 | | BC 08 | 2 | 1 | 2 | Button: Feeder Slot | | |

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|---|----|--------|-------|---|---|---|---|------|--|
| 4 | 0 | | BC 09 | 3 | 1 | 3 | Button: Feeder Slot Request Button | | |
| 4 | 0 | | BC 10 | 3 | 1 | 3 | Indicator: Feeder Slot Request Beacon | | |
| 3 | 0 | | BC 11 | 3 | 1 | 3 | Indicator: Claw Catch Indicator: An LED will illuminate when the | | |
| 1 | 0 | | BC 12 | 2 | 1 | 2 | Classmate: Camera Streaming Output: Stream output from t | | |
| 2 | 0 | | AR 01 | 1 | 2 | 2 | Initialize Encoders (Drive, Elevator and Arm), and Gyro prior | | |
| 1 | 25 | MP, ML | AR 02 | 1 | 1 | 1 | Robot will operate for the full 15 seconds | 1/29 | |
| 2 | 0 | | AR 03 | 1 | 2 | 2 | Robot shall determine Scoring Column and Scoring Peg to target | | |
| 1 | 50 | MP, ML | AR 04 | 1 | 2 | 2 | Using Light Sensors (and Encoders if its warranted), | 1/29 | |
| 2 | 0 | | AR 05 | 1 | 2 | 2 | Move Elevator/Arm into Scoring position from Pre-Auto position | | |
| 2 | 0 | | AR 06 | 1 | 2 | 2 | Move Elevator and Arm based auto switches (all 6) | | |
| 3 | 0 | | AR 07 | 1 | 2 | 2 | Place Ubertube on Scoring Peg. | | |
| 5 | 0 | | AR 08 | 3 | 3 | 9 | Use Camera for targeting the Scoring Pegs | | |
| 5 | 0 | AS | TR 01 | 1 | 2 | 2 | “Zero Out” Integral portion of the PID algorithm. | | |
| 5 | 0 | | MH 01 | 3 | 3 | 9 | Driver Station Requirements for OTHER team: | | |
| 5 | 0 | | MH 02 | 3 | 3 | 9 | Robot Requirements of the OTHER team: | | |
| 5 | 0 | | MH 03 | 3 | 3 | 9 | Programming Requirements of the OTHER team: | | |
| 5 | 0 | | MH 04 | 3 | 3 | 9 | Mechanism Requirement of the OTHER team: | | |