

Program Descriptions

Robot Arm H25

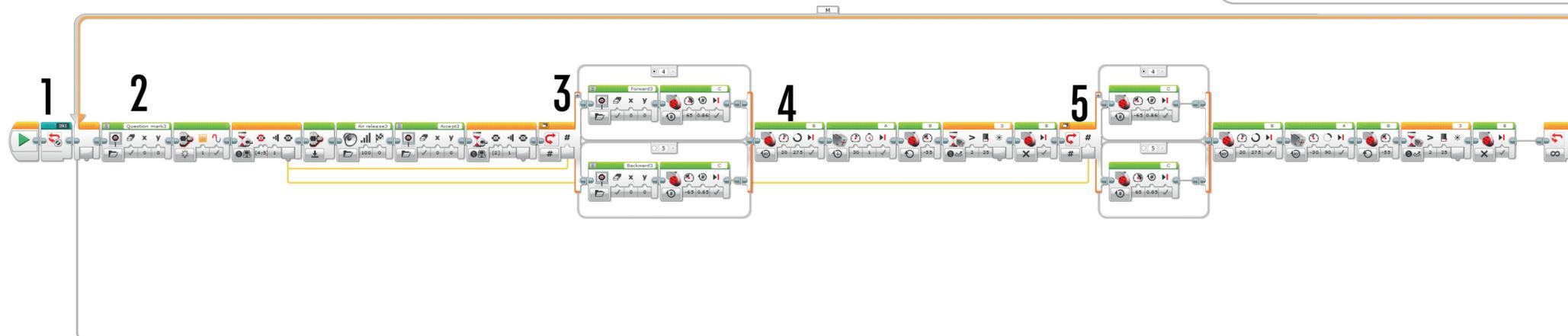


Overview

The Robot Arm Program uses a series of button presses to control the robot. The mechanical limits based on sensors help move the sections of the robot so it knows its absolute position at almost any time.

3 This switch is in Number Mode and takes information from the previous Wait For Block. The movement of the motor is based on the target button press.

5 The second switch works like the previous one. This begins to move the robot back to center. Once there, the arm is dropped and the object released. Finally the arm is raised again to its sensor limit and the program can start again.



1 My Block INI is the initialization of the robot. It sets up the rest of the movements.

2 A display and Brick Status Light cue the robot in waiting position. Next, the robot waits for brick buttons to be pressed up or down, which corresponds to the position of the object. Once pressed, the button information is wired to 2 switches later in the program. Also, the Brick Status Light illuminates, a sound is played, and the display is changed. Finally, the buttons wait for release to continue.

4 This small series picks up the object and brings the arm back up. The A Motor is moved for time to ensure the grip and the B Motor is moved to its limit and stopped.