



End of Week Five!

Code Team Updates:

- Full structure of subsystem code is complete
- Finished full-chained command for shooting balls
- Cleaning up button binding, setting default commands for subsystems to run off of
- Extensive Pathweaving tests for autonomous
- General vision limelight and camera progress

Business Updates:

- Dean's List & Woody Flowers nomination essays are complete & are submitted to FIRST.
- Finalizing Chairman's Essay for submission to FIRST this week.
- Coordinating community outreach opportunities for this summer.

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FLL Update

- FLL Explore and Challenge team shirts were delivered
- Explore Teams continue to work on Core values and Lego models
- FLL Challenge Team 39297, Future Shift had their first scrimmage in which they learned valuable information about what to change for their competition.
- FLL Challenge team will rebuild some of their models after being notified by the judges for competition.
- Robot programming issues have been fixed for the light sensor.
- Videos for scrimmage (in case we couldn't present virtually) were recorded by our proctor Ben , a member from Paradigm Shift.



Glossary

Pathweaving: The Pathweaver program helps us plan out a path for the robot to follow. On the Pathweaver application, we draw out a line for the robot to follow and the application gives us values that we can put into our code that allows the robot to follow the path we drew.

Limelight: The limelight (see right) is a camera that detects reflective surfaces. By using the limelight, we can more accurately detect areas like where to shoot the ball. This can help improve accuracy and speed of the robot.

