



Ship update

Ready or not we are done. As of 11:59:59 last night we had no choice but to place the robot in a bag and tag with a numbered zip-tie. After the number is recorded and signed for, we are only allowed to work on it (well for the most part.) Since we are going to a two day district event and not the three day regional events that we have previously attended FIRST allows us a total of six hours of work on the robot the week before our competition. Despite the weather attempting to knock us off our game we got a predominantly functioning robot in the bag at 11:59

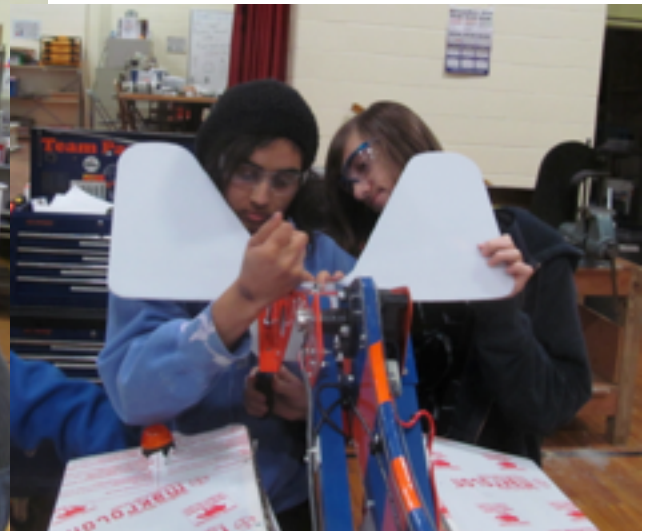


We had the electrical and mechanical components ready in plenty of time. However, the robot was not being compliant with the programing code. Through hours of hair pulling and the devoted work of Burt Smith gets one of this weeks shout outs for his patient work with the programing students that permit the robot to be responding correctly by the time it had to be put away. Additionally we had time to put our customary electriquarium red and blue lights. Thanks to Chris Koenig's diligence, another recipient of

this weeks shout out, our robot's electronics are neatly wired throughout the robot and the robot is neatly embossed with team colors and spirt while also having complete arms and mechanical components.



Prior to the robot going on lock down, there was an electroaquarium that needed to be constructed, code that needed to be updated and arms that needed to be fabricated as well as bumpers which needed to be finished. Every one was wiring, labeling, cutting and coding right up until the last minute.



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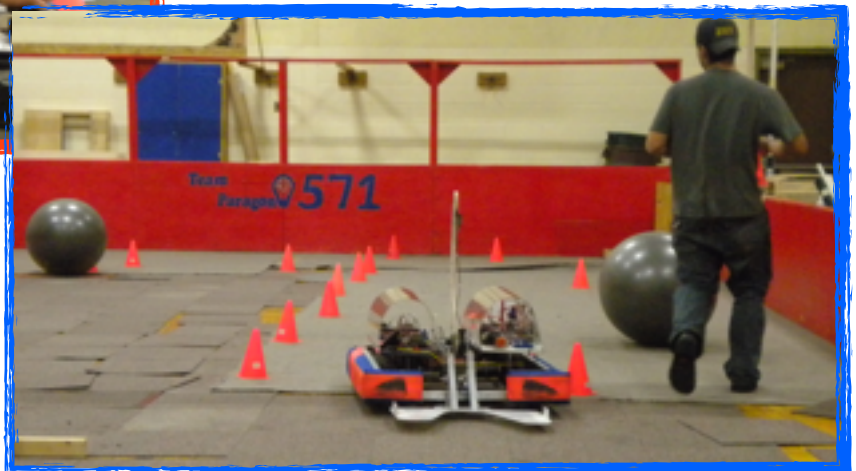
0 - float totalAngle = 0;
0 - float TURN-MAGIC = 0 ..... ? degrees/sec
5000
0 - float start_x = GetJoystickX();
0 - float start_y = GetJoystickY();
0 - float lastTime = getTime();
0 - float startTime = getTime();

AS
VS
DO
float timerNow = getTime();
float time_c = timerNow - timeLast;
float deltaAngle = time_c * MAGIC * twist;
totalAngle = totalAngle + deltaAngle;
float current_x = sin(totalAngle);
float current_y = cos(totalAngle);
float speed_x = current_x * start_x;
float
  
```





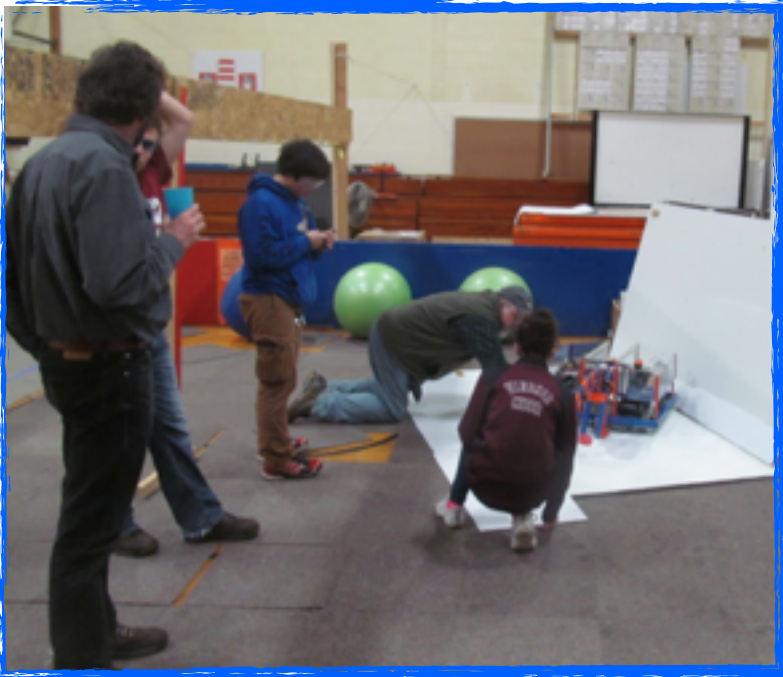
After shoveling out the lot, the drive team took time to practice driving Julie before getting to work on the last minute changes and details to Dr. Seuss before we had to part ways.



Additionally, this week we have continued preparing for the competitions in the other subgroups.

Imagery

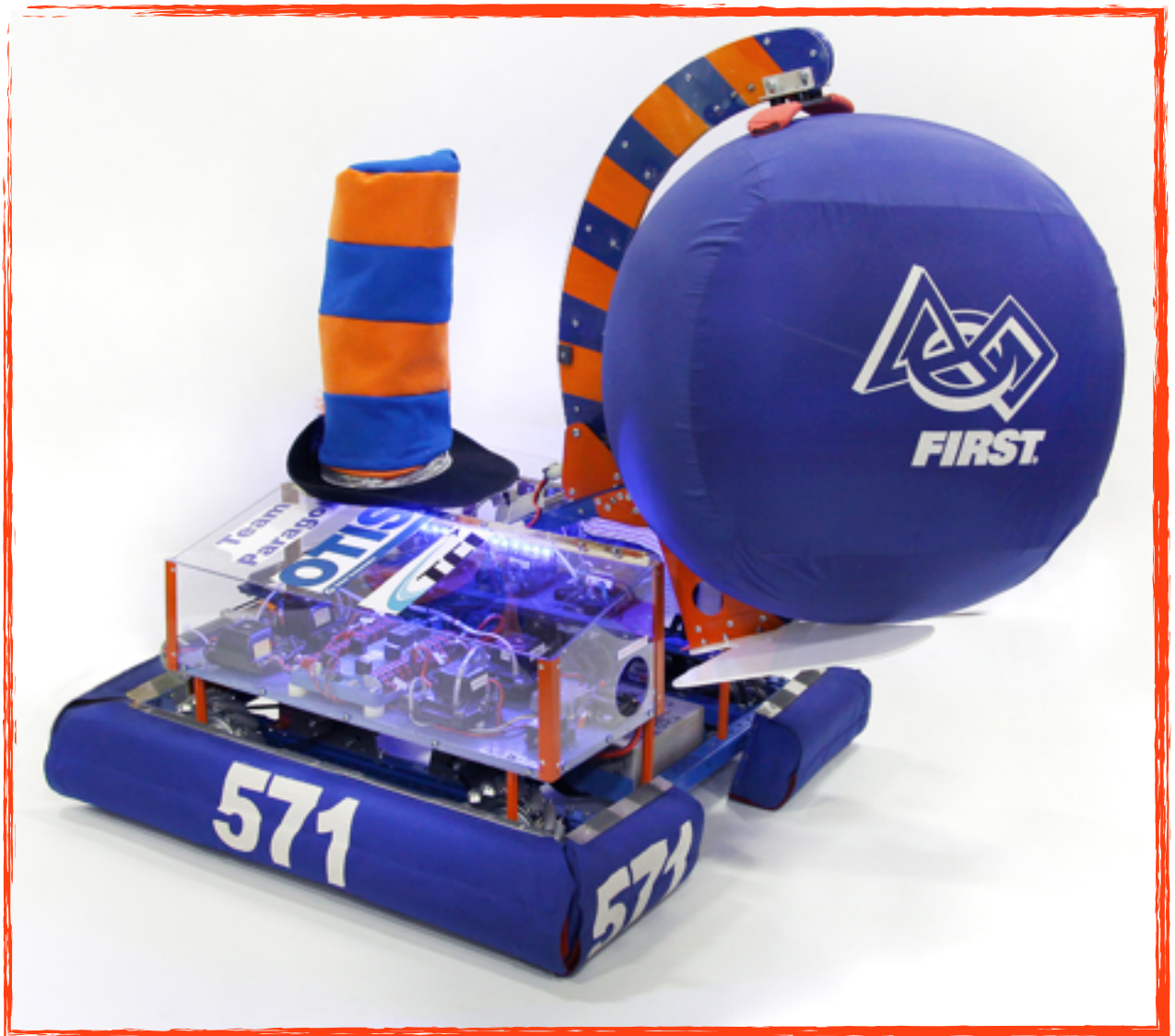
The bracelet work continues on strongly thanks to Elyse Carroll's drive and leadership. One set of awards are nearing completion so that they will be ready in time for our



first competition. We have started to paint them and gotten the labels written up to send off for printing. We have also designed the labels for the robot to share our primary sponsors, tell who we are and to show our

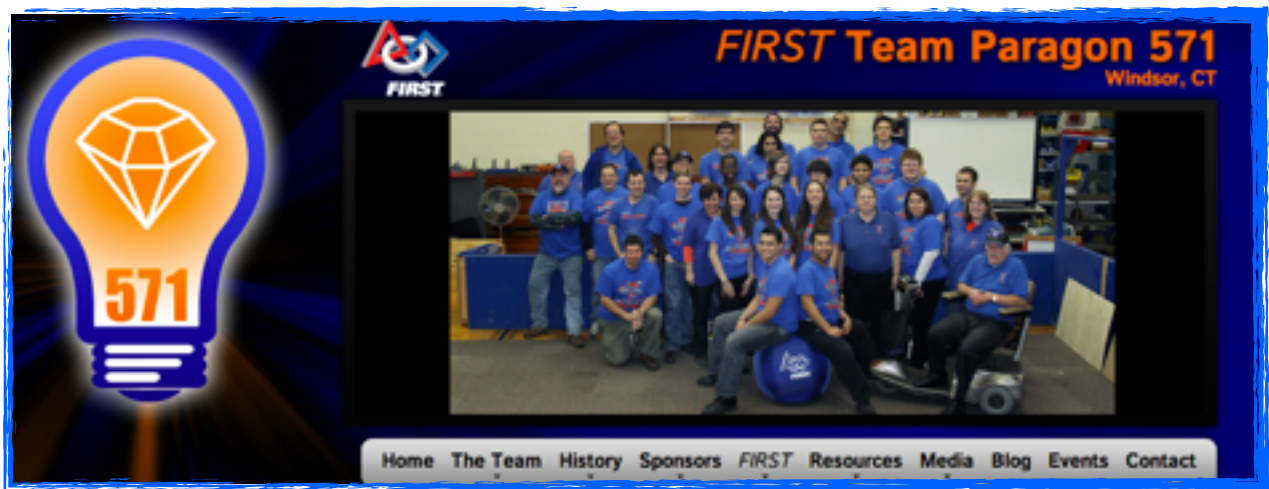
theme for the year. Also, our book has is in the final

stages of production thanks to Michele Eleveld for her illustrating efforts. Our button designs and printing has been completed. Now to assemble them is the next task. We also are working on the “design” aspect of the pits. Before the robot could be bagged, Dr. Seuss had to pose for his photo session. He had a lot of paparazzi to contend with. Thanks to George Petro, we have Dr. Seuss’s portrait ready for display.



Web

We are collecting interviews to create the video. Also, we are continuing to work on updating information on the website. As we are gaining more sponsors we are continuing to update the sponsor page on our website to



acknowledge and show our appreciation.

Up Coming Event

Groton District Competition: March 8th and 9th

Hartford District Competition: March 29th and 30th

Continue to watch for the weekly updates on the blog to watch our progress.

Follow us at:

@TeamParagon571



www.team-paragon.org



Contact us by email at: teamparagon571@att.net