



Prize Winner

Computer Programming, Apps & Robotics Year R-2

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Report

The aim of my entry. I build this robot because it can help us carry bags to school and back to home.

The type of my robot.

robot with Lego
Mindstorm
and I make
the program
on Lego Mindstorm
App.

Instruction of
using my robot.

the robot on.

next link the

blue tooth on

the App. Last

run the program.

Explanation

Explanation of what
the section of

the program do.

First I put start module it

will let program

ready to run. Next

I put switch I

set in fared sensor

then set compare

last set proximity.

Then I put a

move steering in

the switch under

a tick that

means when

the sensor see

me it will follow

me. I also put

a move steering

under the cross

and set the

steering into

minus 100 that

means when the

sensor can't see

me it will

turn around until

it can see me.

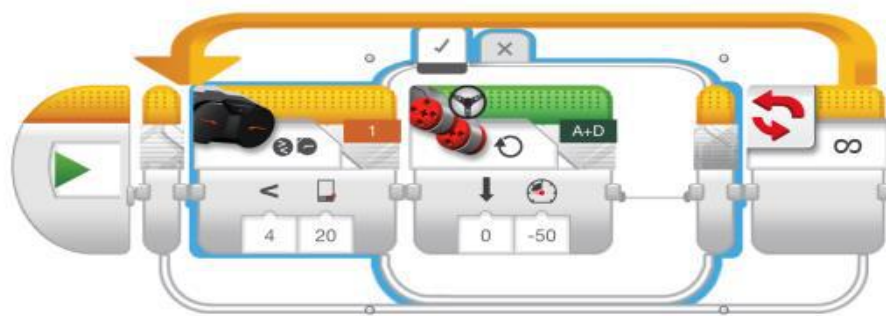
Last I put

a loop around

the switch

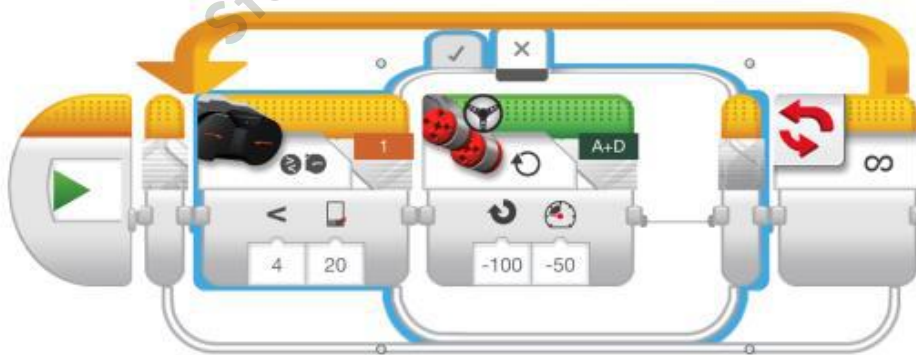
so it can a

follow me.



No EV3 Brick

A	B	C	D
1	2	3	4



No EV3 Brick

A	B	C	D
1	2	3	4

Review Record

Day 1 I put two

Motor wheels one

at the front right

one at the back

left. But it didn't

work well because

it can't stand

probly. So next

I change my

plan it is using

One Motor wheel

at the middle
back and one
front wheel made
by my self without
a motor. End of
day

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day 2

I make the
program of my
new way fixing my
robot. I try it. It can follow
me but when
I turn, the
robot can't turn
with me. so I
need to change
my plan again.

My program
has a start
module and a loop
module. In the
loop module I use
a wait module and
choose infrared sensor
then set compare
last I set proximity.

Then I set
ready the Threshold.

value that means

within the

Threshold value the

sensor can interact you.

after that add

Large Motor module

and set "ON for seconds"

then I set

the power it is

minus 50. Last I

set the seconds it is 5.

Now I give my robot
a name it is
Mr. black. When I
start, Mr. black will
follow me when Mr. black
can't see me it will stop
and it also can't
turn. So I will
change my plan again.
End of day 2

day 3. This time

I use two motor

wheels one at

middle back and one

at middle front.

Now I try the

program. It didn't

work well because the

wheels are

going the wrong

direction so I need to

change my plan

again. I then use

two motor because

I thought with

two motor can

turn with me.

Then I change

the direction

of the front

motor so it will

go round the same

derction as the back motor.

So I think the
robot have no problem

so I will need
to make a new
program again.

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day 4.

I build the program
of my new

way making

my robot

my program first

I put the start

it can let

the program

ready to run

then I put

switch I set

"Infrared sensor" then

"Compare" last

"Proximity"

last I put

move steering

under the tick

that means if the

sensor see me

it follow me.

I also
put I move steering
under the cross
I set the steering
into a manner
that means
when the
sensor can't
see me
it will turn
around until

it can see me.

last I put

loop so it

can always

follow me.

but the robot

still can't turn

with me. But I

trust the program

have no problem

so the robot have

Problem so I

have to change
my plan again.

End of day 4

day 5. day 5 I

put two motor

wheels at the

back and front wheel

without a motor

when I finished

I try the program.

It can follow
me! Finally it can
follow me. It also
can follow me turn.
Because I found that
when I run the
switch module,
only one motor
is working. So
that's why I put
two motors at the back.

