

# BARELANG63 Mechanical and Electrical Description 2023

Muhammad Revalba Gingsang, Tajdar Hal  
Ata, Muhammad Imron Shodiq, Muhammad Yusup, Nadhif  
Suherryman and Ridwan Bahari

Batam State Polytechnic,  
Jl. Ahmad Yani, Batam, Indonesia  
barelangkrsbi@gmail.com

<https://brail.polibatam.ac.id/Barelang63/index.html>

**Abstract.** To participate in RoboCup Medium Size League(MSL) 2023, BARELANG63 builds a new generation of robots MSL robots. Our mechanical system is described in this paper regarding the electrical system, mechanical systems, and structures used in robots. The system and structure range from kicker mechanism, dribbling mechanism, and vision system.

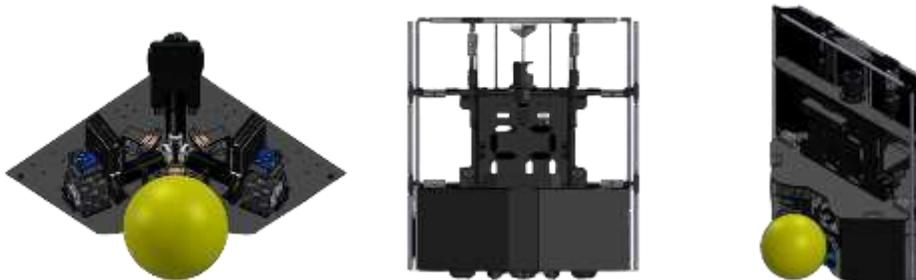
## 1. Mechanical Structure

We developed the latest robot design shown in Fig. 1. We made a layered frame design for the layout of the ball handle system in the first layer and the electrical system in the second layer. The size of the robot is 48 x 47 x 75 cm with a weight of about 35 kg. for our robot frame made of stronger aluminum sheets.



**Fig. 1.** BARELANG63 Striker Robot

We developed the latest goalkeeper design as shown in Fig. 2. We made a layered design where the first layer contains the driving motors, dribble system, and kicker system. The second layer contains the electrical system. The weight of the robot is around 35kg. For robots, we build with raw materials and ISO standards.



**Fig. 2.** BARELANG63 Goalkeeper Robot

### 1.1 Frame

In our omnidirectional wheeled robot, we use the omnidirectional wheel, with three-layer omnidirectional wheels can be seen in Fig 3. The whole body of the robot is made of a sandwich structure aluminum sheet and uses an aluminum round bar with a thickness of 12.7mm so it can withstand pressure and can make the robot stronger.



Fig. 3. Sandwich Structure

### 1.2 Ball Handler

#### - Kicker Mechanism

The BARELANG63 robot uses a solenoid plunger mechanism for the kick system dan for the robot keeper only uses a lob shot to throw the ball as far as possible. The plunger material we use is iron and aluminum to give a strong structure and we added some useful bearings for the smooth return of the plunger the kick mechanism design is shown in Fig. 4

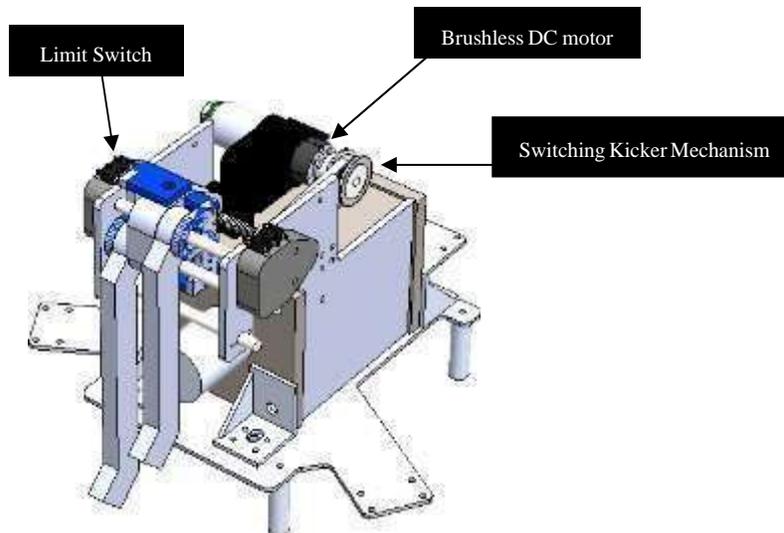


Fig. 4. Kicker Mechanism

#### - Dribble Mechanism

In the dribble system, we use a PG28 DC motor shown in Fig. 5. The main material used for this dribbler system is aluminum which gives it a strong structure. We have also adjusted the dribble angle so that it is relatively facing the front of the robot to allow the dribble to rotate around the front area of the robot.

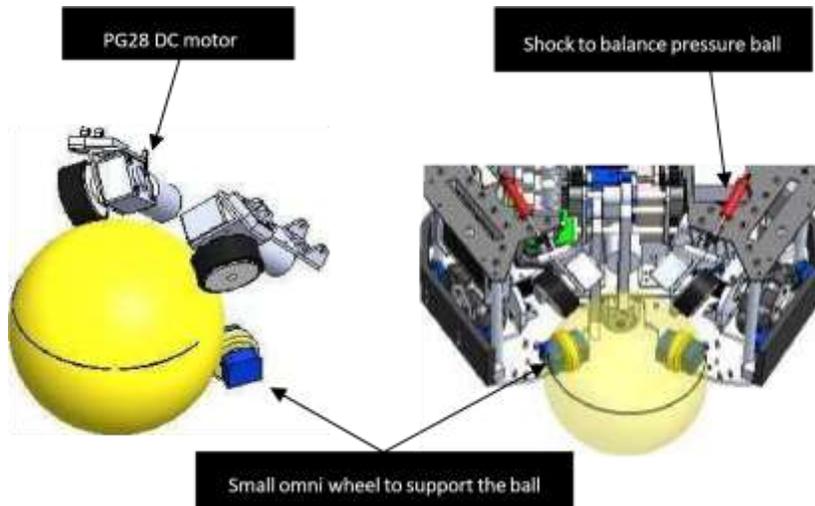


Fig. 5. Dribble Mechanism

### 1.3 Vision System

In the vision system, we have made a design using an aluminum structure as camera support, for the camera protector we use an acrylic tube to protect the camera and mirror from ball kicks. In the previous design, we used stainless steel as a camera protector, and it created a blind spot on the vision system that could interfere with the previous vision structure we used aluminum hollow which is very thin and not very sturdy to be used for the vision system structure, for the vision system structure design, shown in Fig. 6.

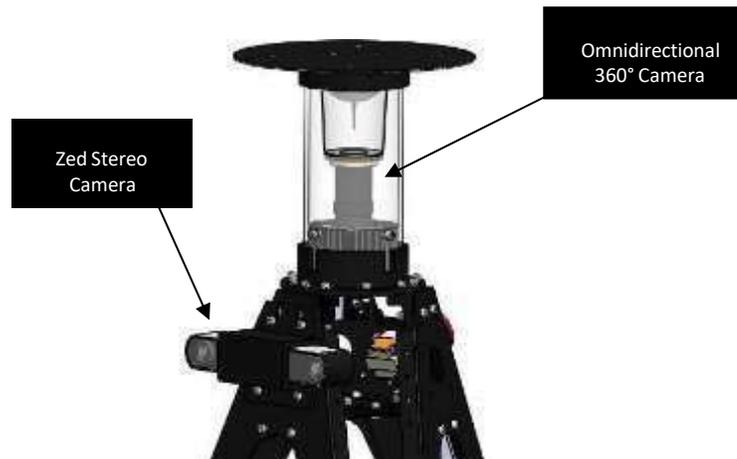
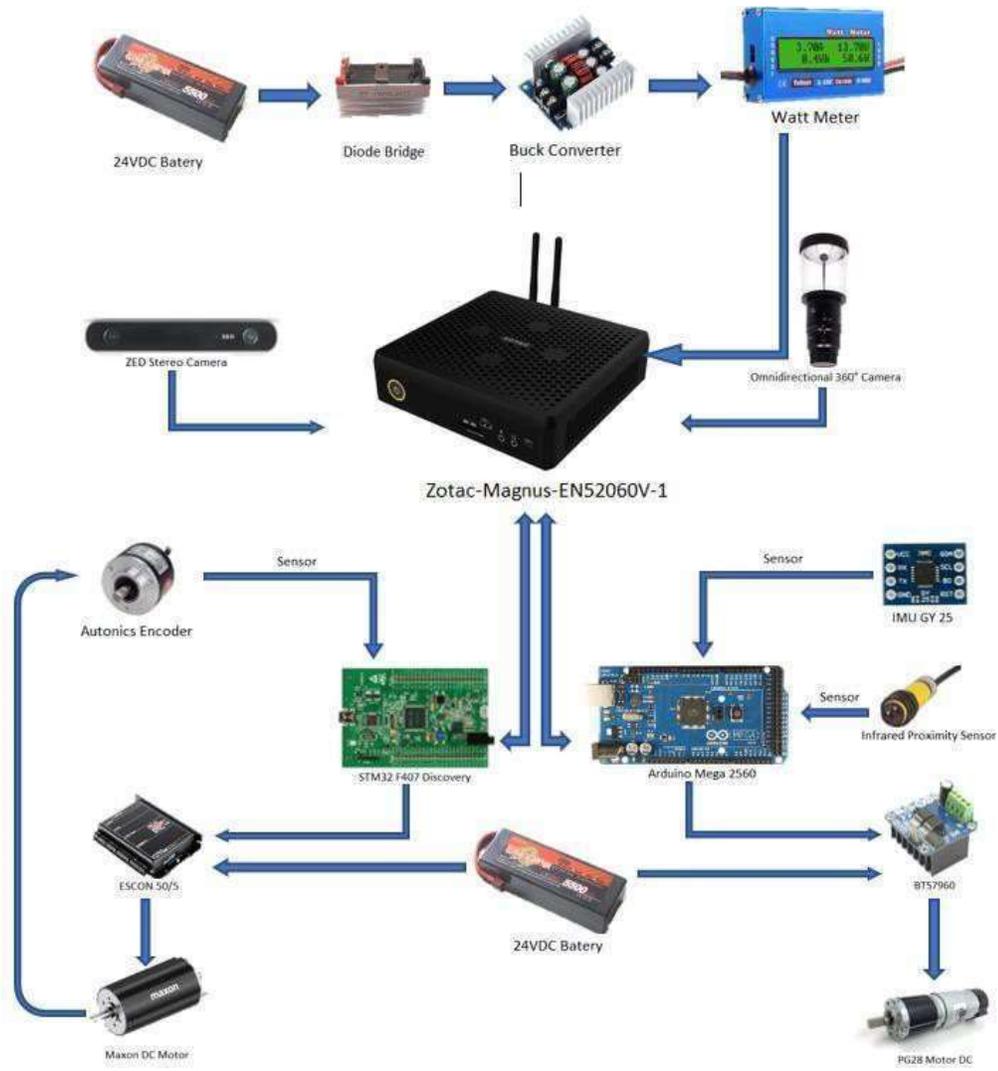


Fig. 6. Vision System Structure

## 2. Electrical

This year our robot changed from a mechanical as well to an electrical aspect. Especially in the electrical system, last year our robot used an inverter (DC to AC) to activate the PC by changing the input from a 24VDC battery to a voltage of 220 VAC, then the inverter was replaced with a buck converter (DC to DC) changing the input from a 24VDC battery to 19.5 VDC according to the input for the PC / laptop used in the robot as shown in Fig.1 below. In addition, in this paper, we also explain the electrical system on the Arduino Mega2560 and STM32F407 Discovery, as well as the electrical system on the BARELANG63 robot kicker. this robot uses 3 lipo batteries, namely 2 uses 6-cell lipo batteries (24 VDC) which are for supply to PC/laptop, Maxon Motor as well as PG28 DC motor. One uses a 3-cell lipo battery (12 VDC) which is for the kicker system in our robot.

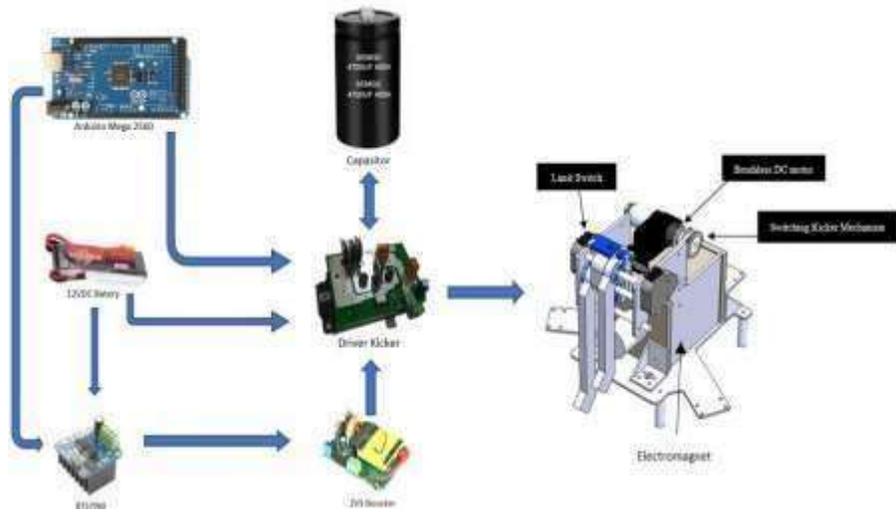




**Fig. 8.** System electrical structure

### 1.2 System Kicking

To be able to kick like a human, our robot uses a solenoid mechanism, namely by applying a high voltage to the solenoid so that it can produce a large magnetic field. To produce this high voltage, it can be seen in Fig. 9 below which to control a strong system, the slow kick on our robot is to use an Arduino Mega 2560, on this micro, it is also used to adjust the BTS7960 driver, where this driver is to activate the ZVS BOOSTER (step-up) from 12vdc to 450vdc, after the ZVS BOOSTER is active it will go to the next stage, namely to IGBT after the ZVS BOOSTER was active, the resulting voltage will be stored in the capacitor, if the capacitor is fully charged it is ready to be used to be able to use the voltage stored in the capacitor. In this case, we use the IGBT as a high-voltage electronic switch where the voltage will be used in the solenoid to generate an electromagnetic field so that the robot can kick.



**Fig. 9.** System kicker structure