

Student Name: \_\_\_\_\_

Unit No.

4

**Part I.** Place the letter of the key term next to the correct definition.

Term	Definition
	A one-joystick robot drive code that uses the x and y axes for locomotion, enabling the operator to operate a robot drive system much like a one-joystick arcade/video game.
	Refers to any of the six labeled origins of input on the VEX Transmitter.
	Factory initial control program code loaded into the VEX (or other) Microcontroller.
	Uses logic (programming software) to receive commands and interpret signals from the Transmitter and/or sensors that control a robot's movement and functions.
	Refers to any of the eight ports for connecting Motors and/or Servo Motors to the VEX Microcontroller.
	A device that passes signals from the Transmitter to the Microcontroller for interpretation.
	A two-joystick robot drive code that typically uses the y-axis (up and down) only for locomotion. Each joystick controls a single side of the robot drive system.
	Primary input device used for tele-operation of a VEX (or other) robot.

**A.** Receiver    **B.** Arcade Style Drive    **C.** Default Code    **D.** Tank Style Drive  
**E.** Microcontroller    **F.** Transmitter    **G.** Motor Port    **H.** Channel

**Part II.** Fill in the blanks.

Some robots utilize software and logic to run fully autonomously, without any human input. Other robots use some sort of \_\_\_\_\_ device so that they can be controlled by a human driver.

The \_\_\_\_\_ is the primary input device used.

The \_\_\_\_\_ wirelessly communicates signals to the Receiver Module (RX), which is located on the robot. The RX passes these signals to the \_\_\_\_\_, which uses logic (programming software) to interpret them. This then sends signals to the motors, which move.