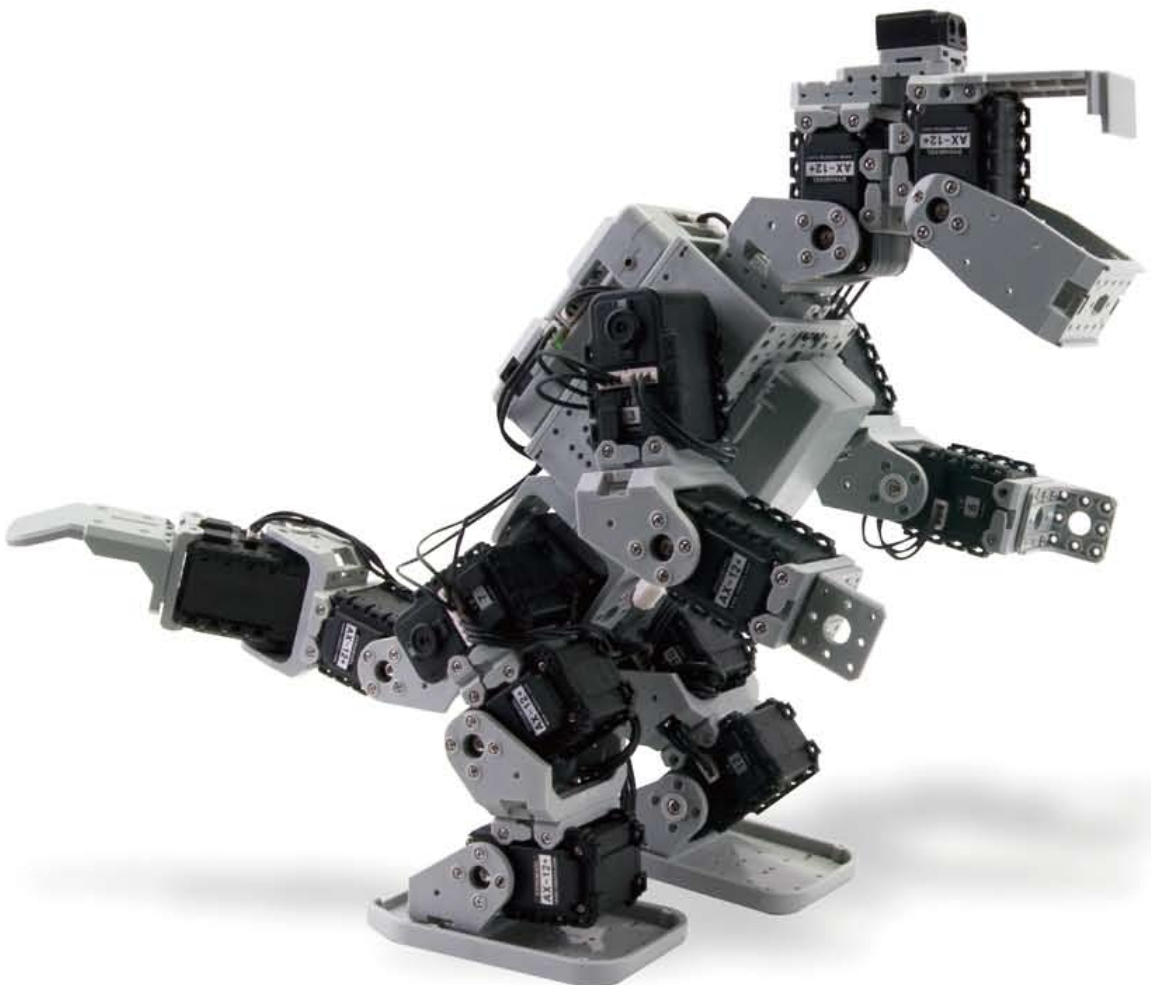
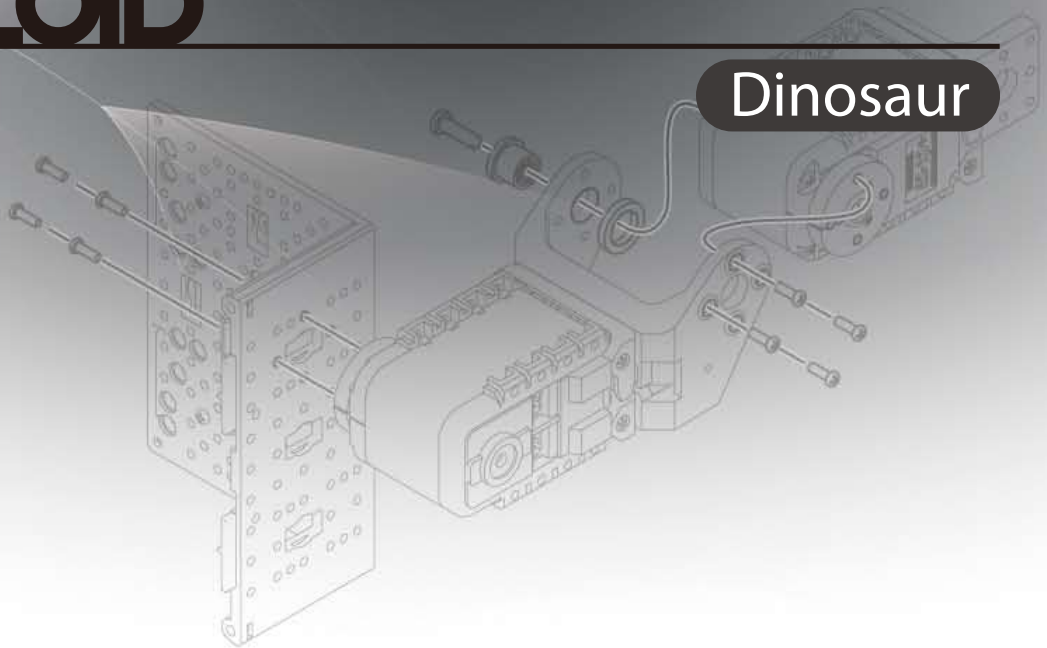
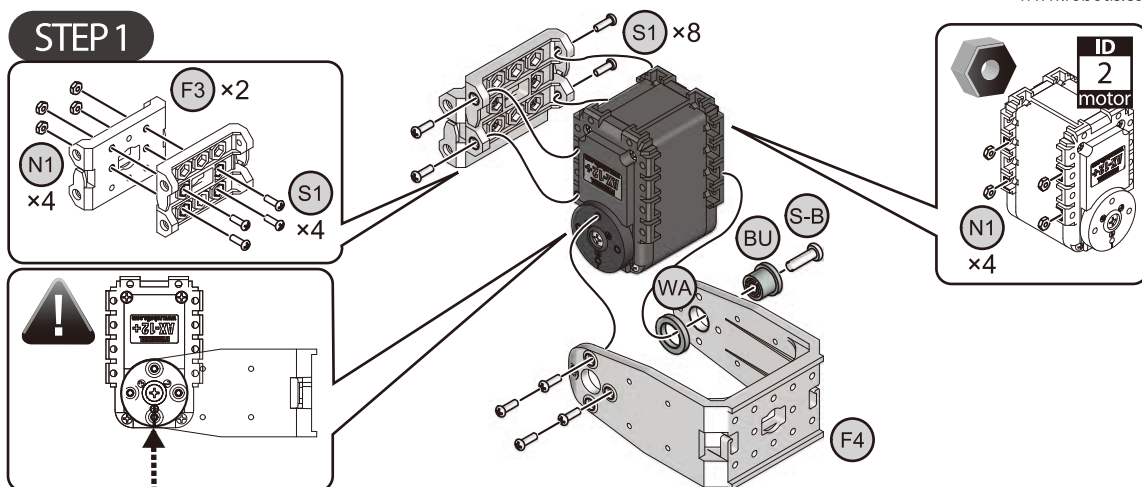


BIOLOID

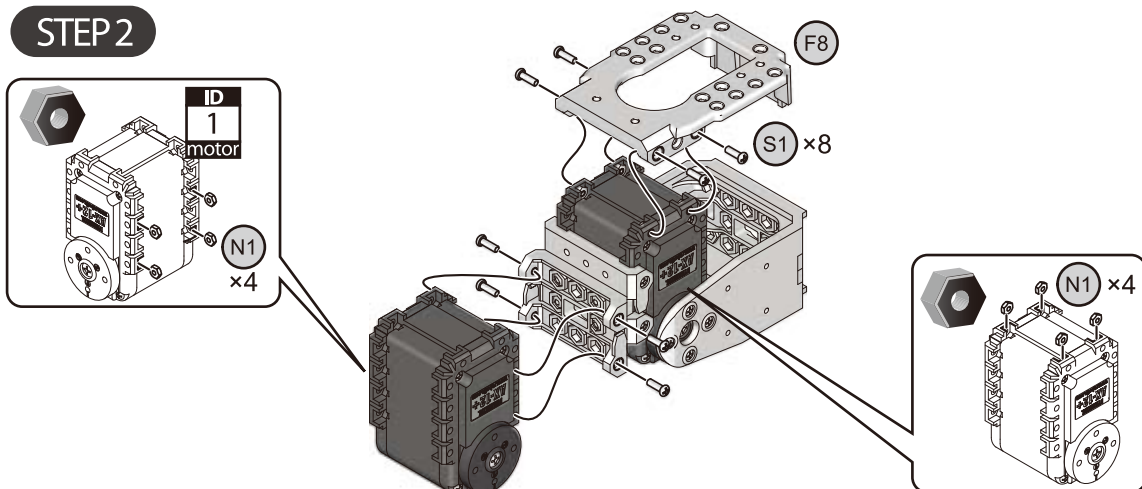
Dinosaur



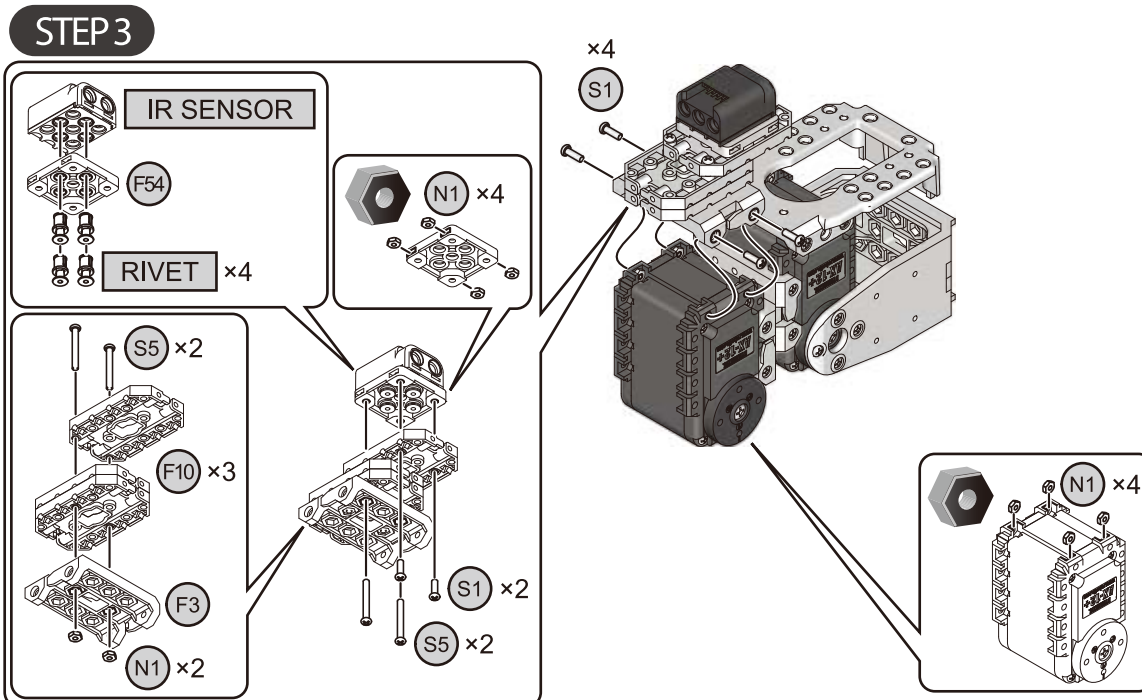
STEP 1



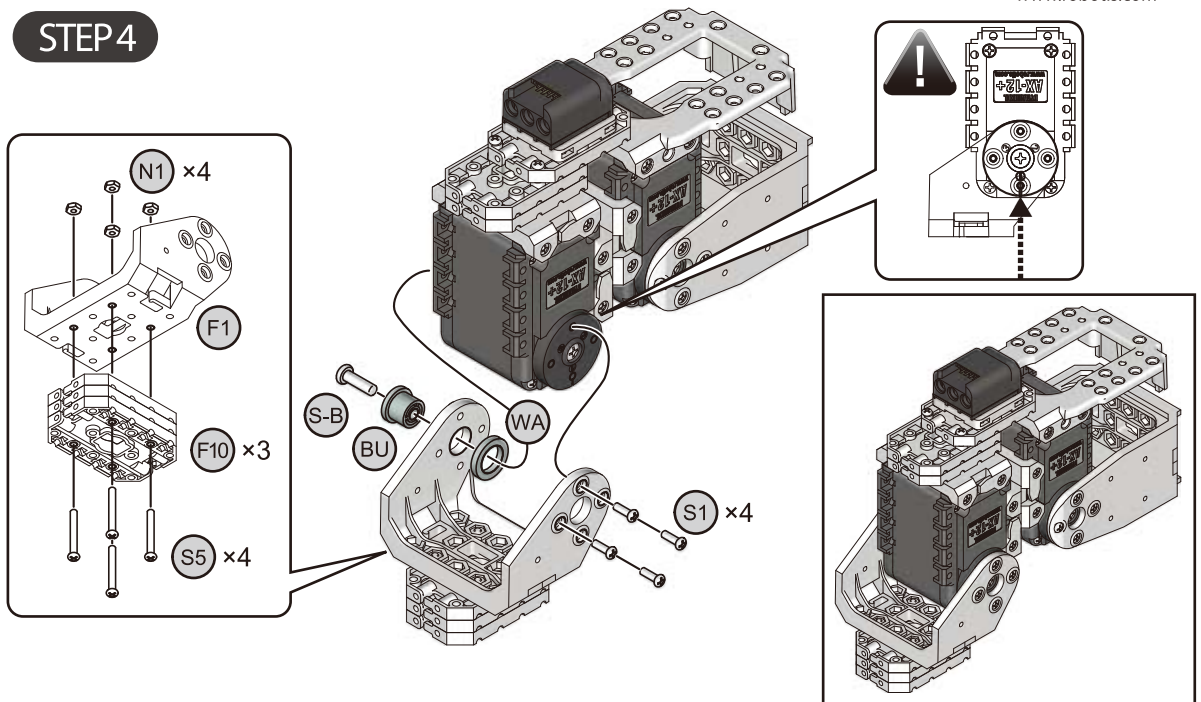
STEP 2



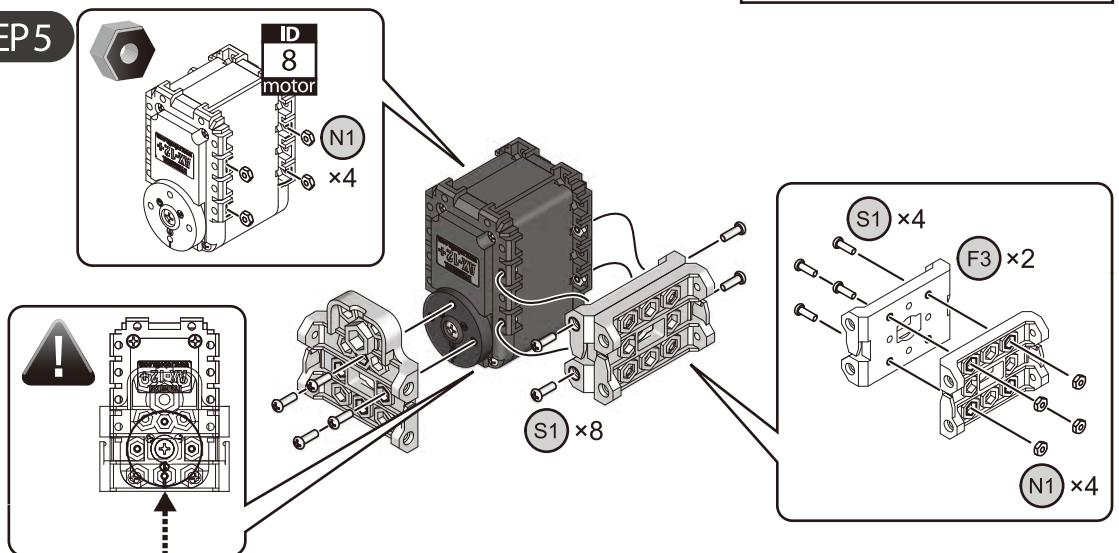
STEP 3



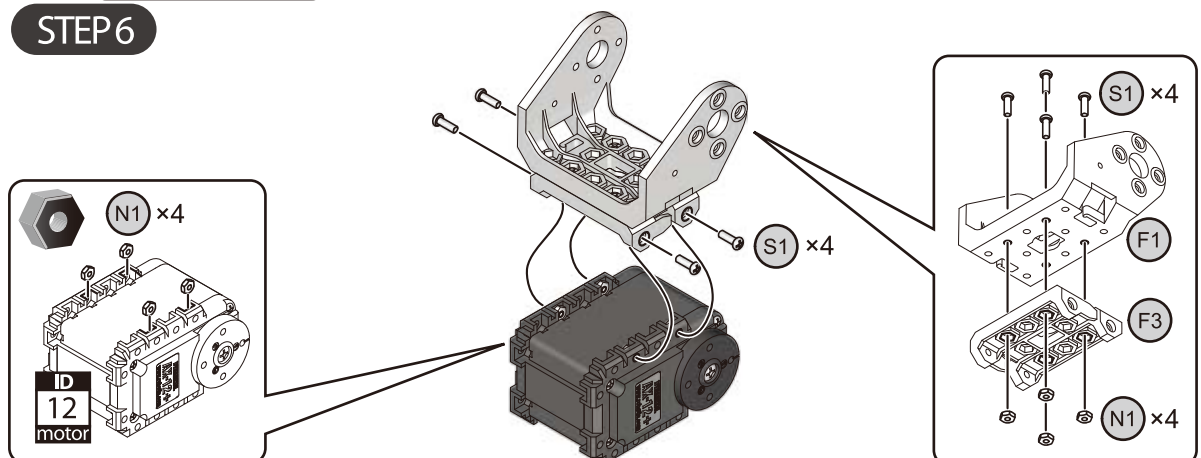
STEP 4



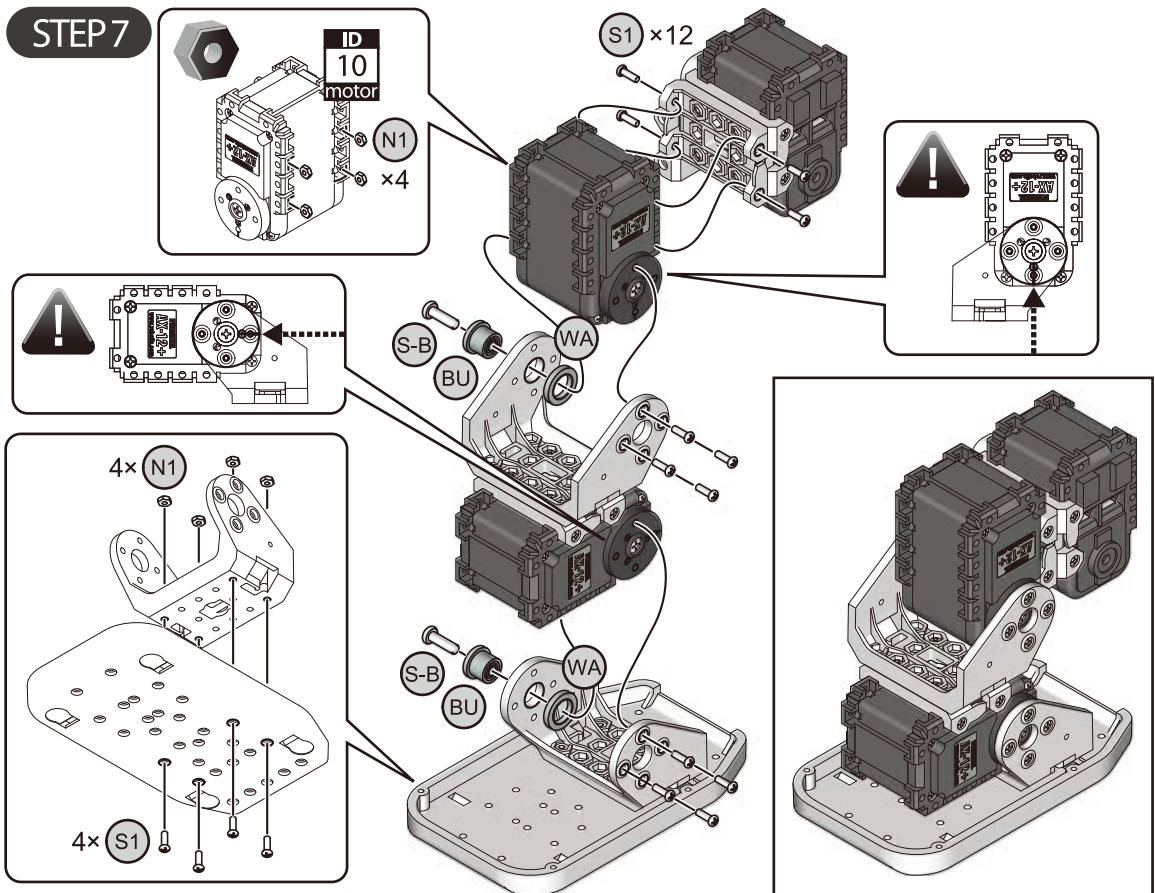
STEP 5



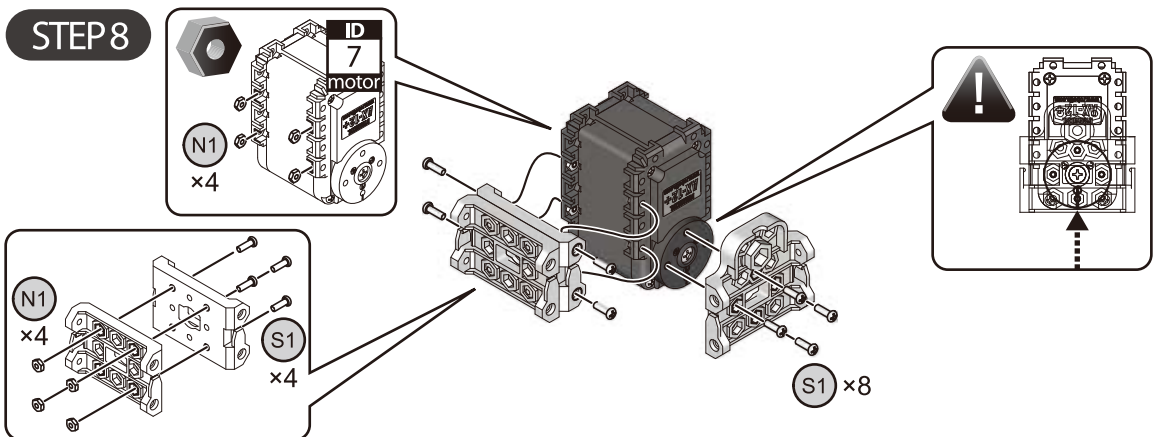
STEP 6



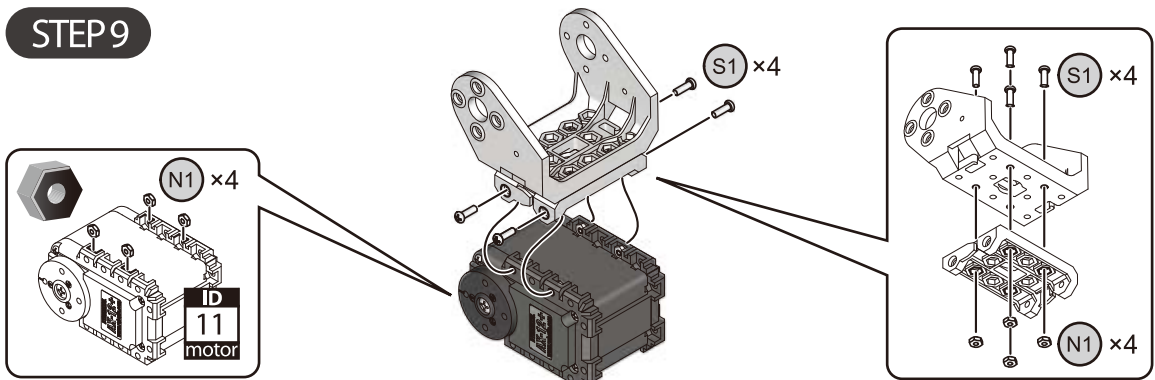
STEP 7



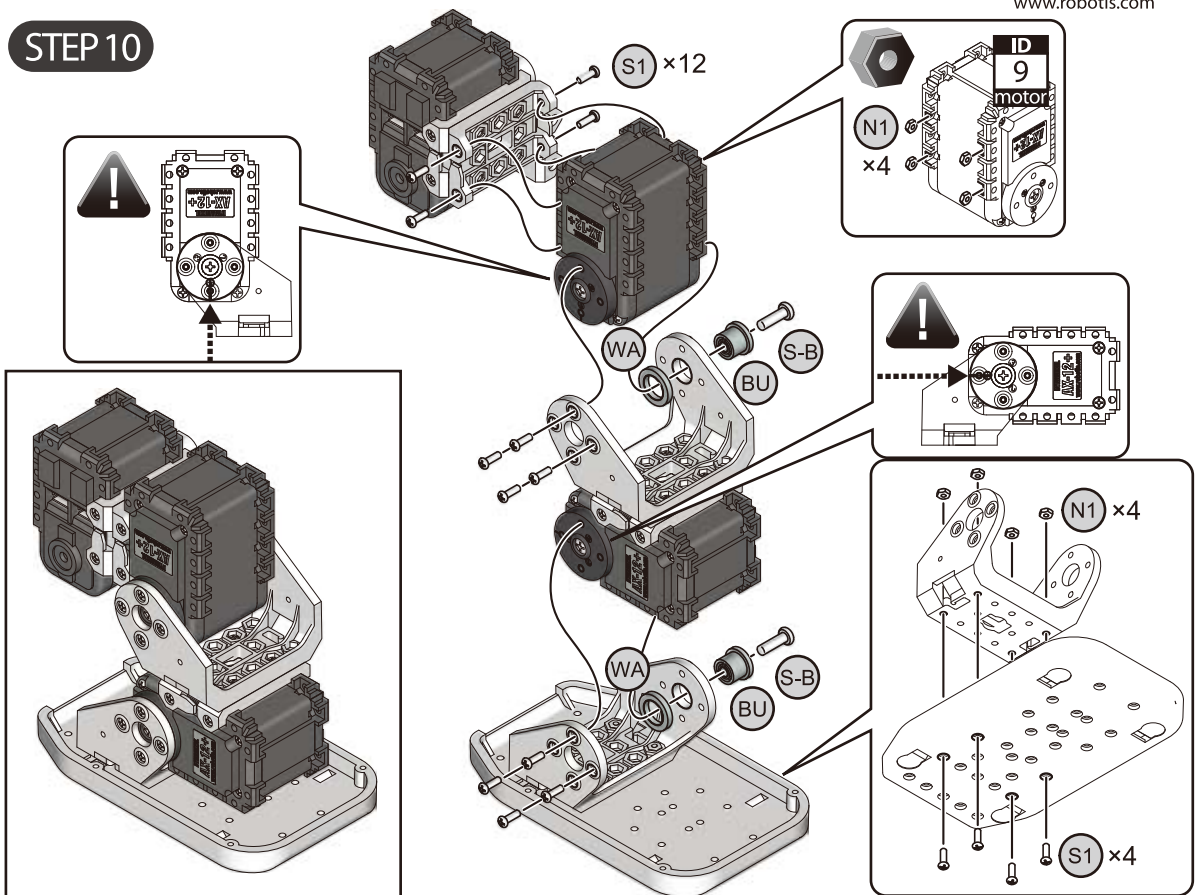
STEP 8



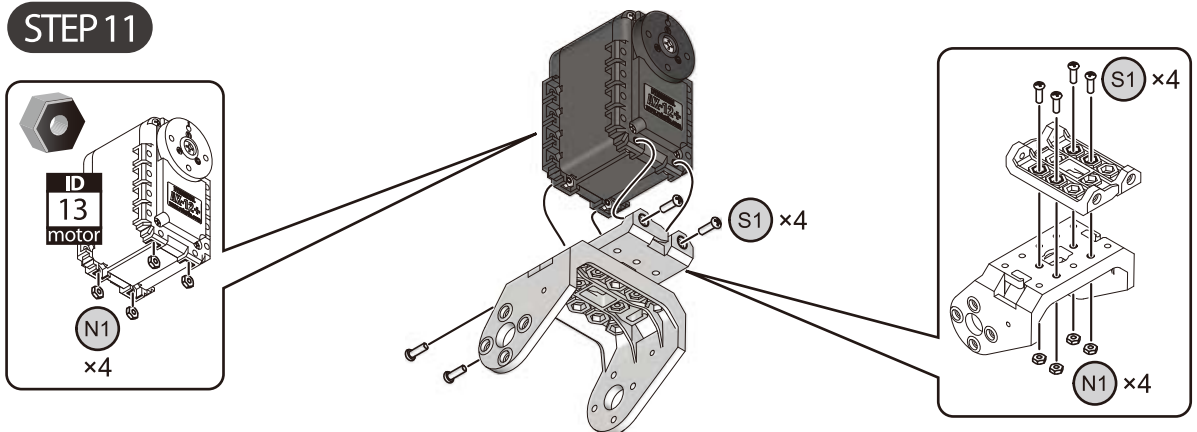
STEP 9



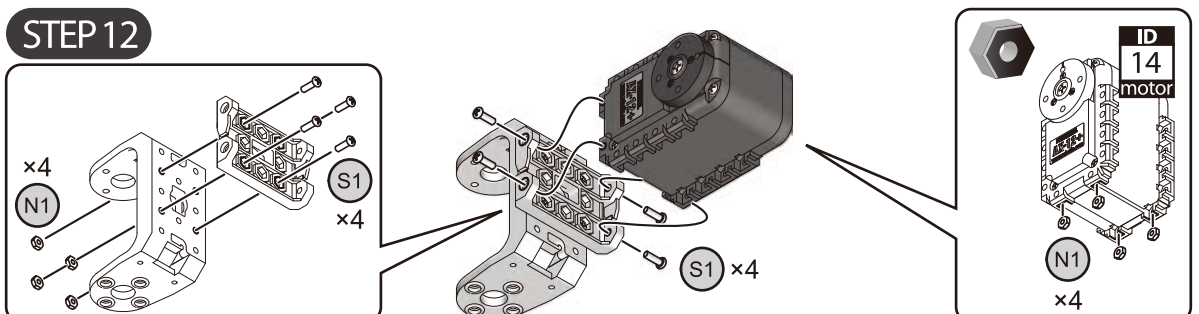
STEP 10



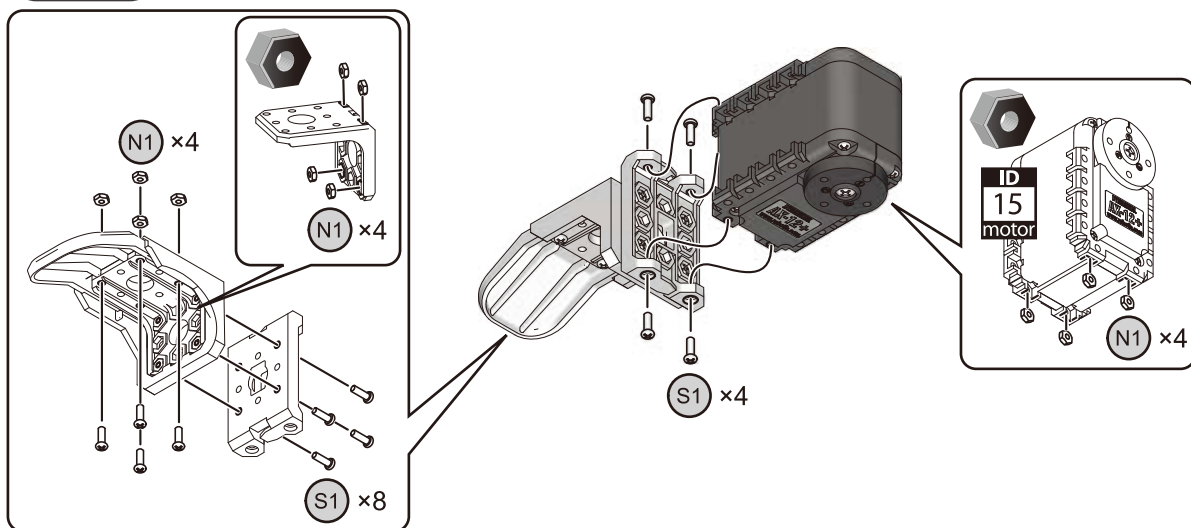
STEP 11



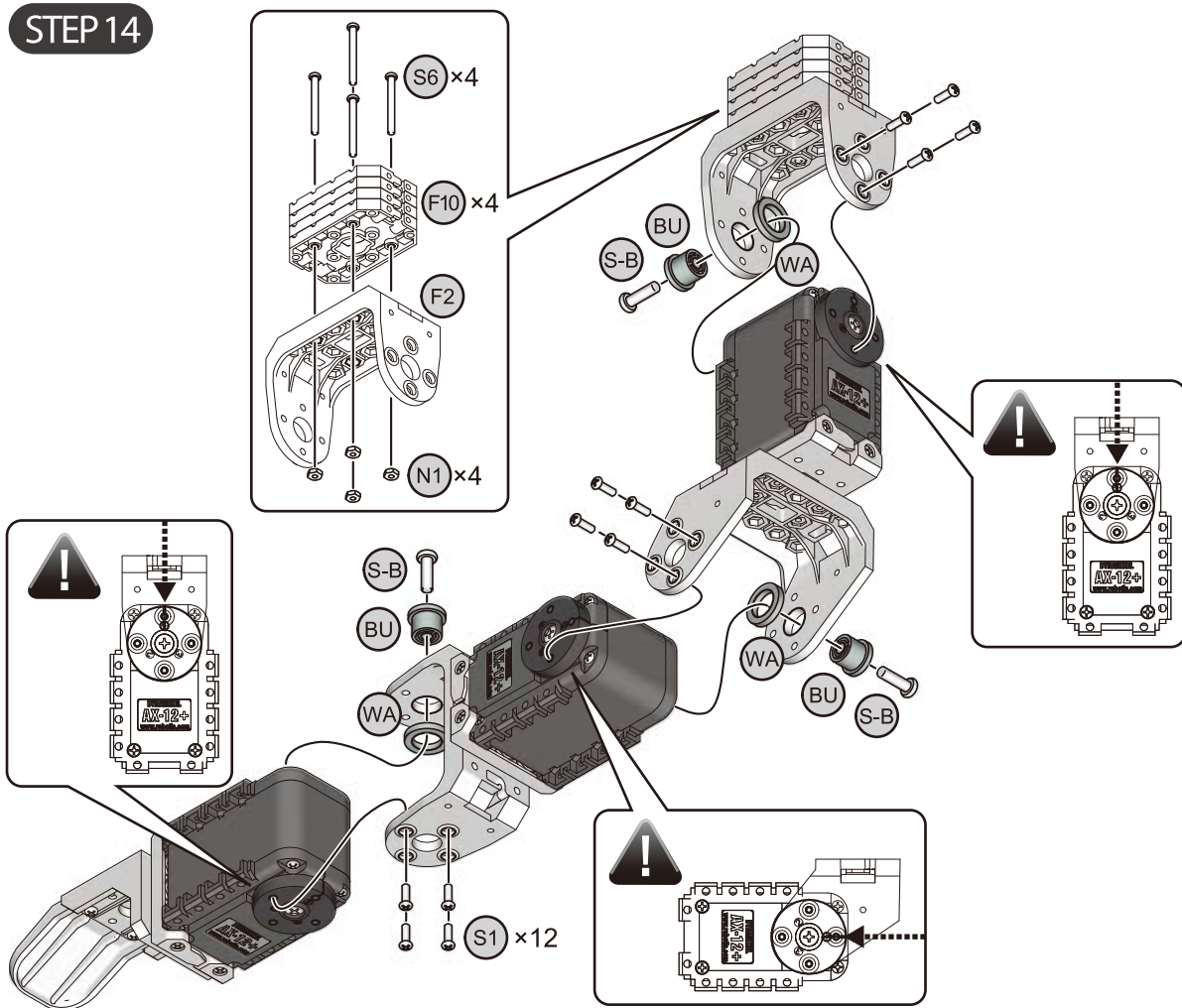
STEP 12



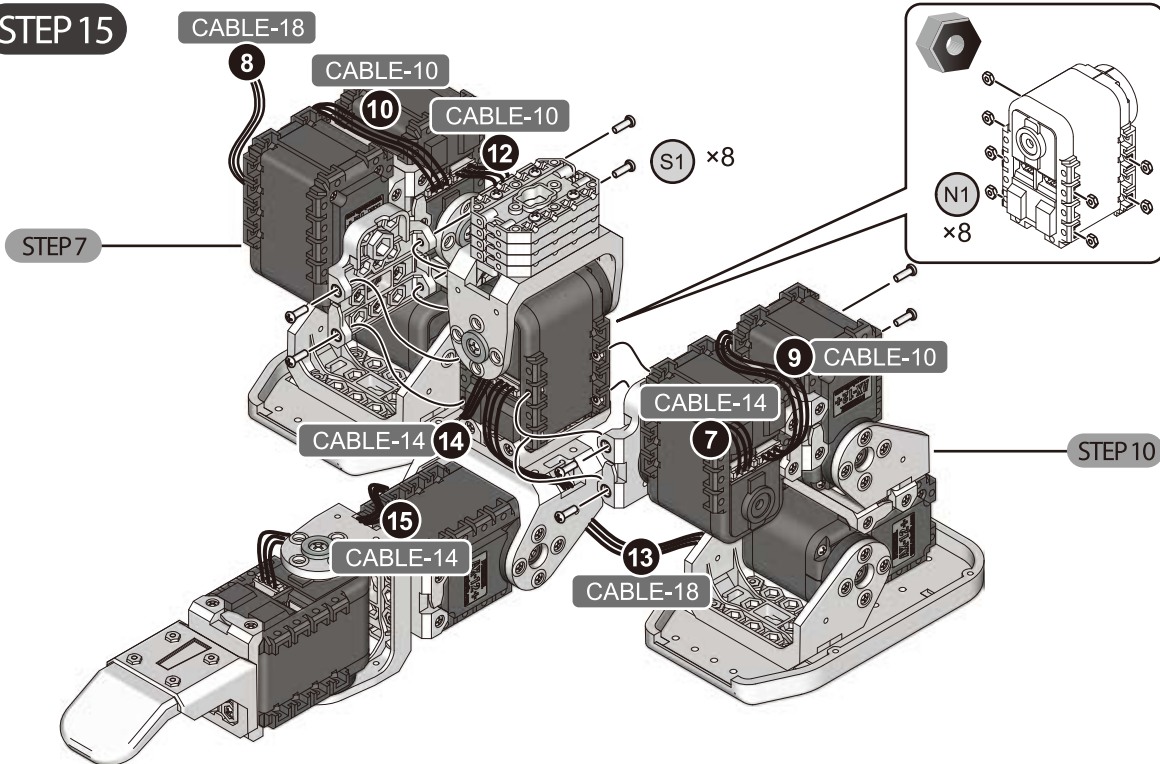
STEP 13



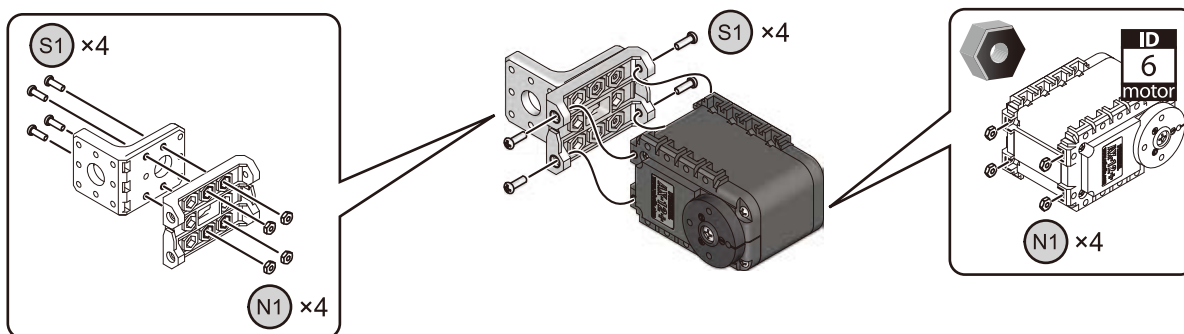
STEP 14



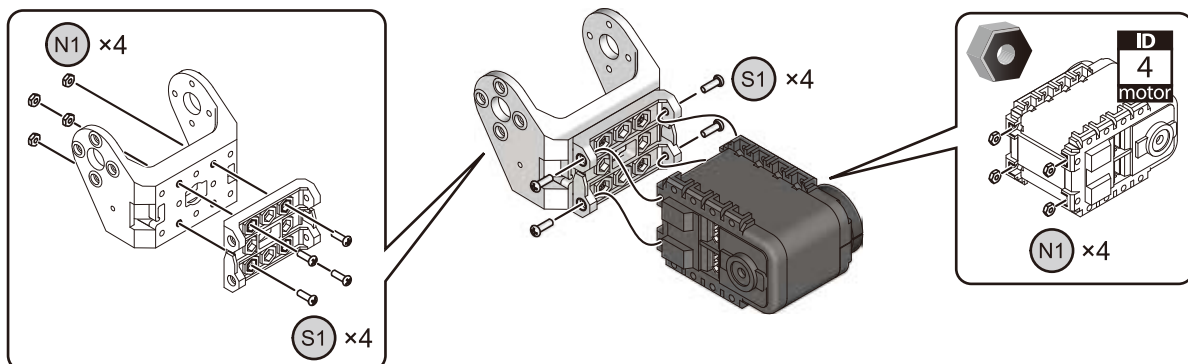
STEP 15

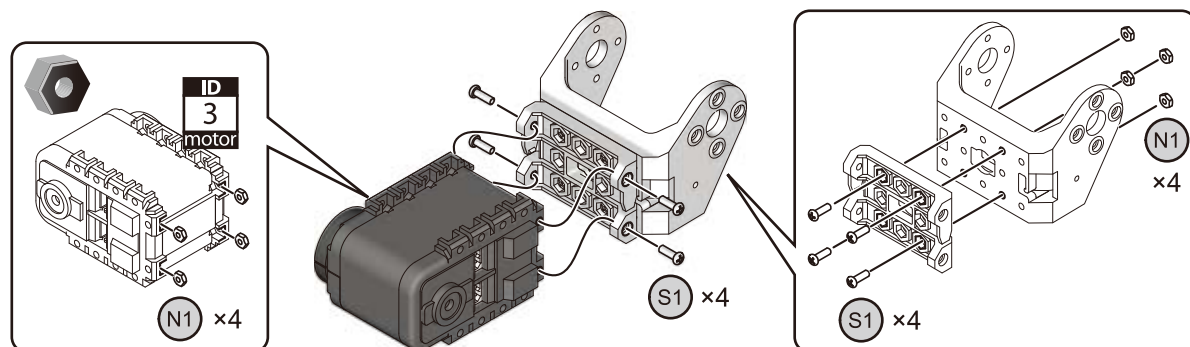
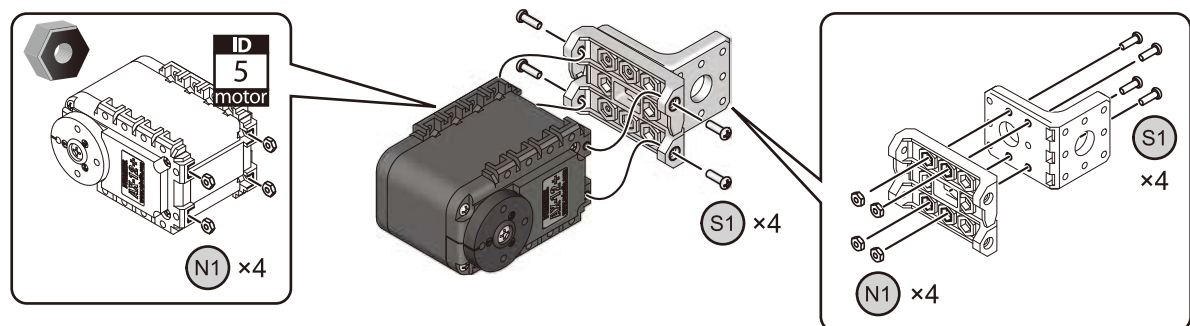
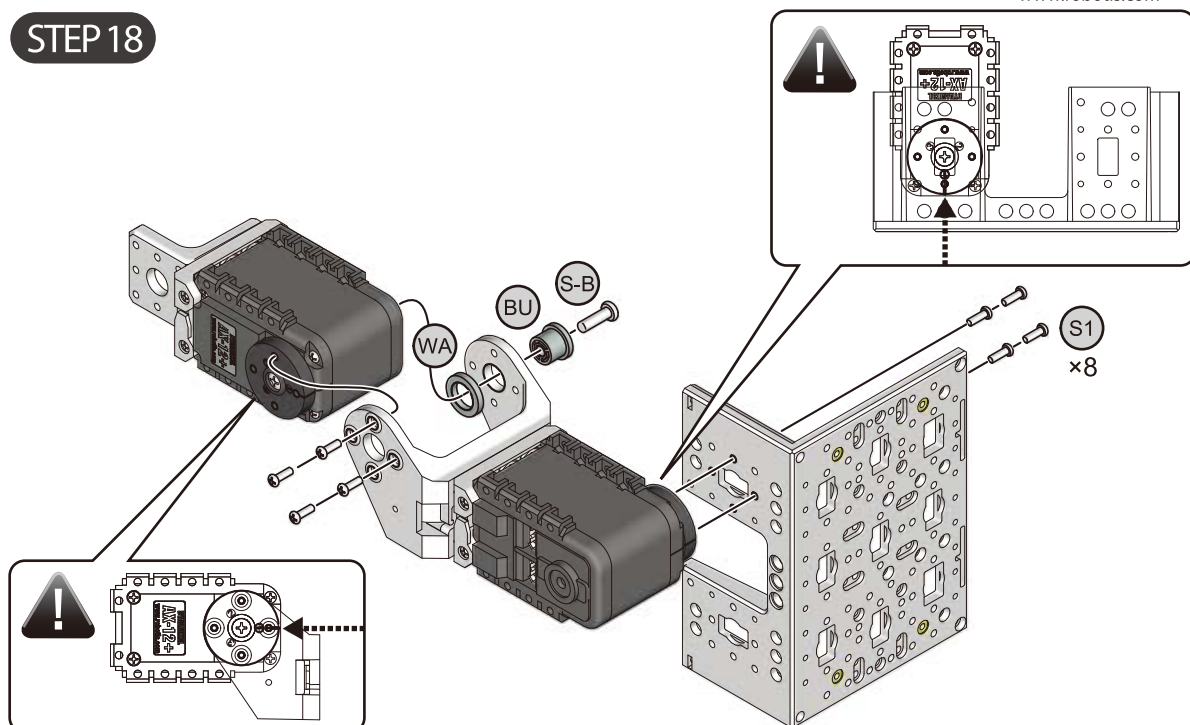


STEP 16

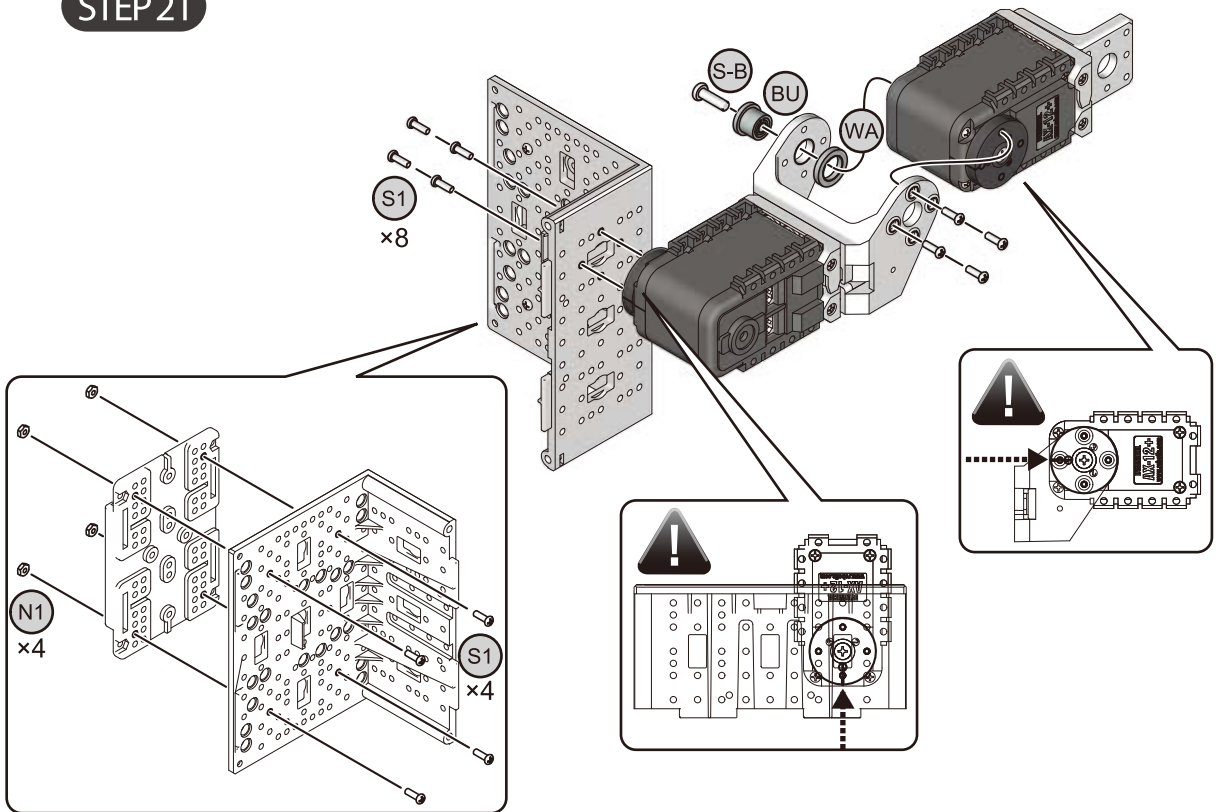


STEP 17

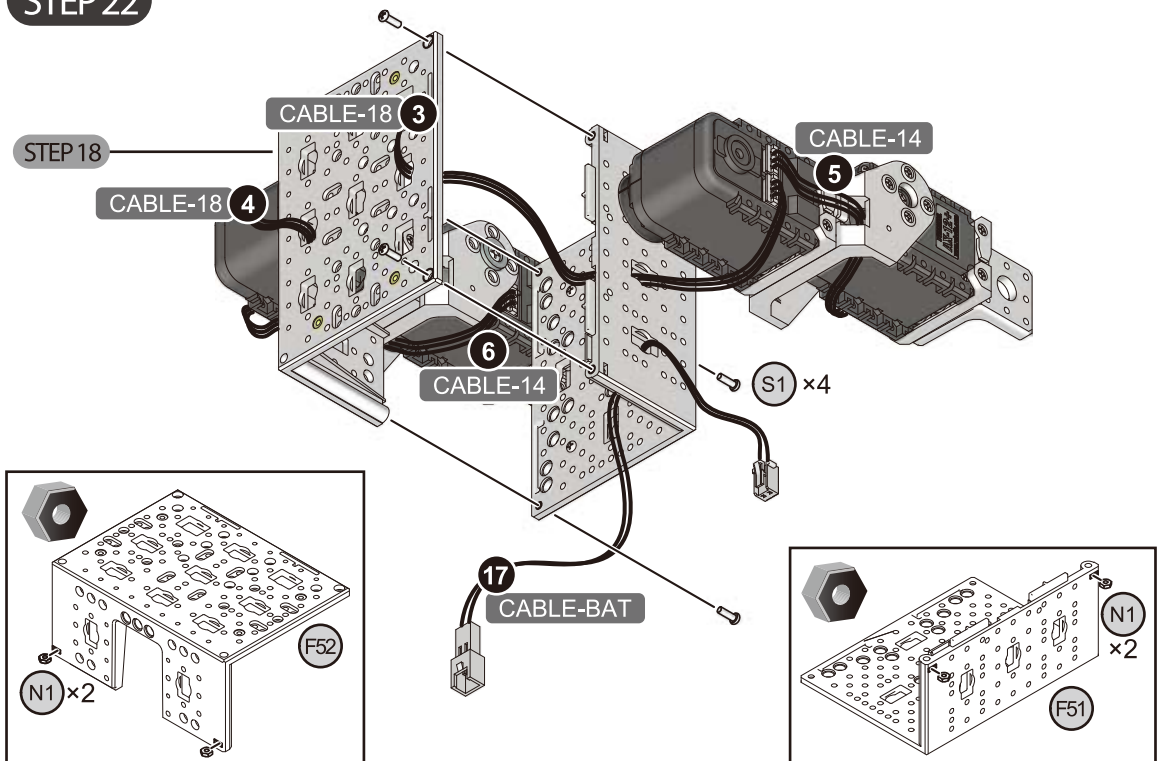




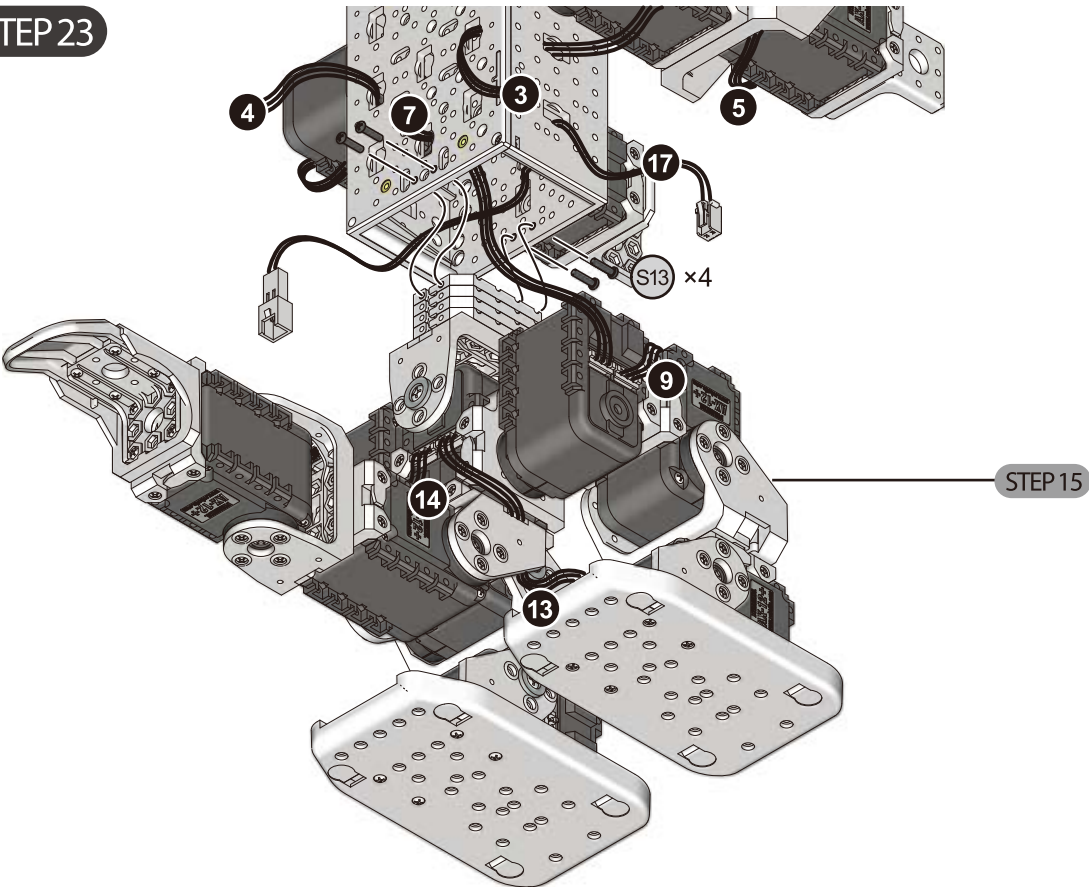
STEP 21



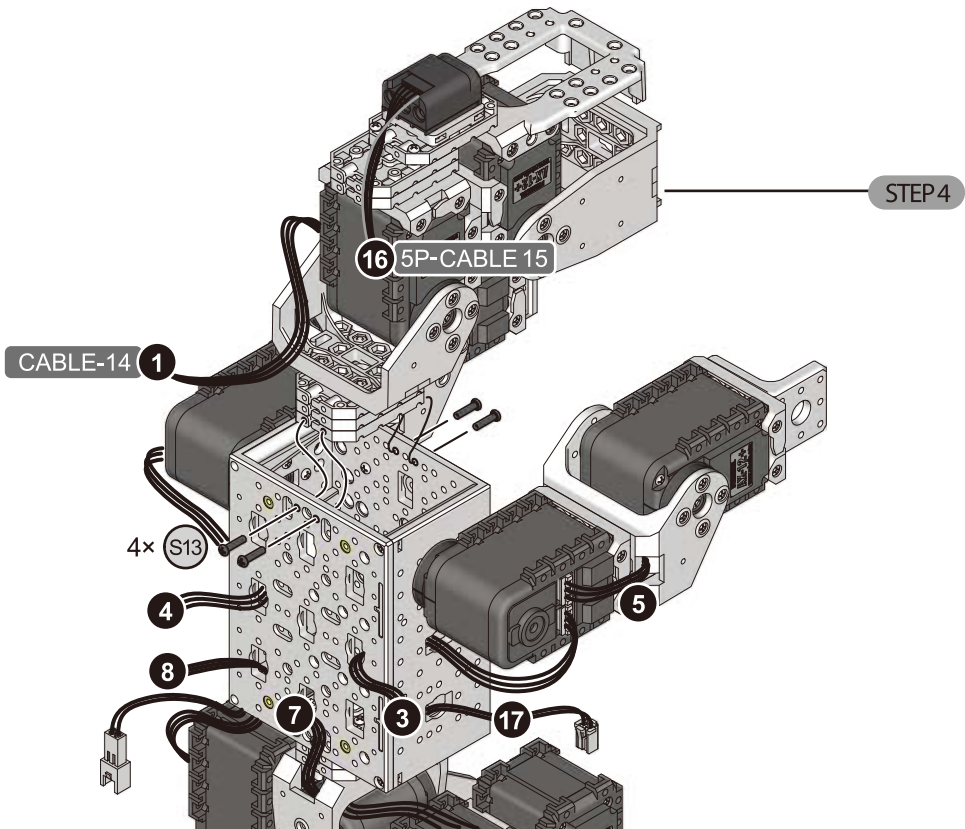
STEP 22



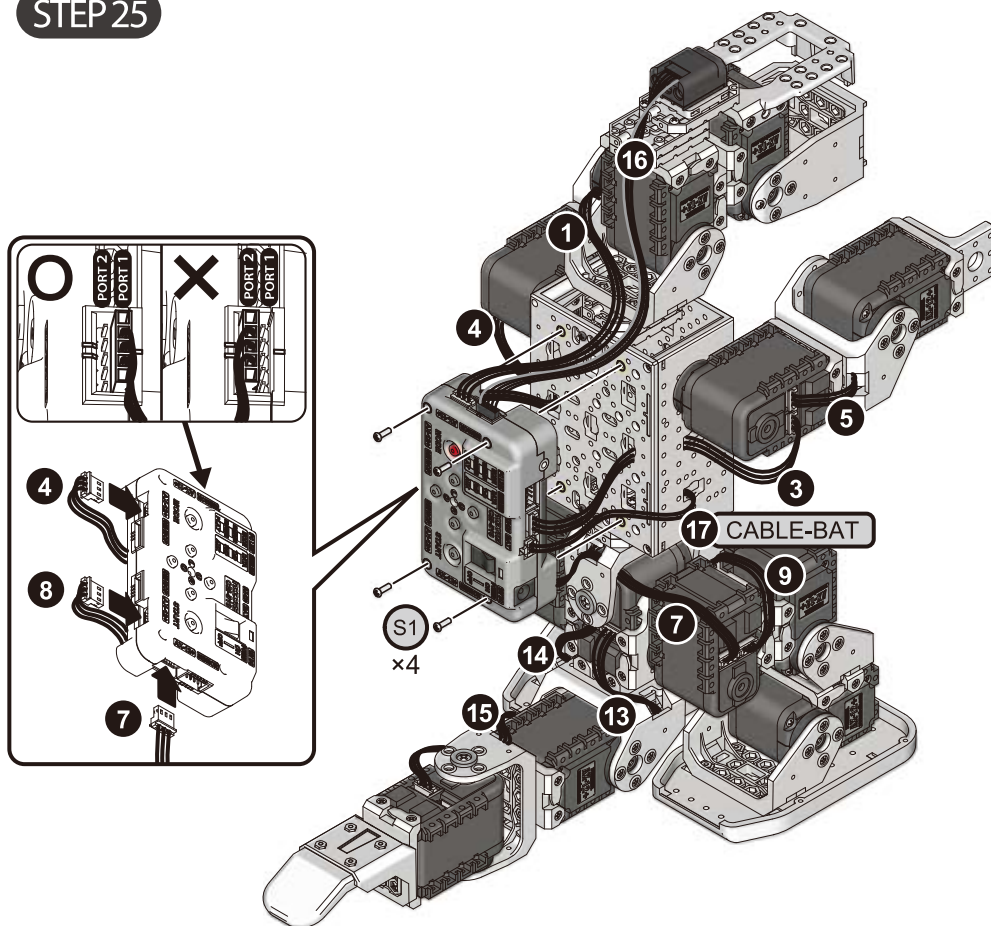
STEP 23



STEP 24

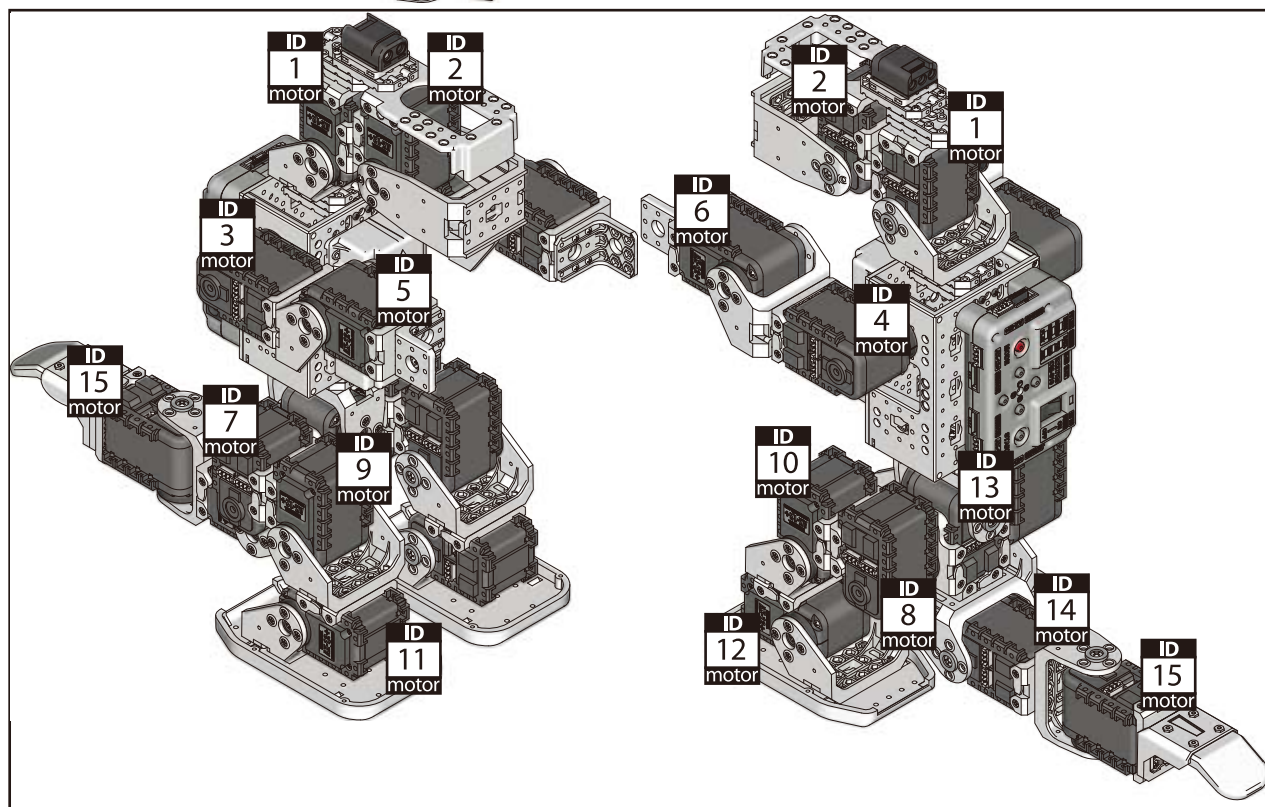


STEP 25



ID 1 motor	◀ 1 CABLE-14 ▶	CM-510
ID 2 motor	◀ 2 CABLE-6 ▶	ID 1 motor
ID 3 motor	◀ 3 CABLE-18 ▶	CM-510
ID 4 motor	◀ 4 CABLE-18 ▶	CM-510
ID 5 motor	◀ 5 CABLE-14 ▶	ID 3 motor
ID 6 motor	◀ 6 CABLE-14 ▶	ID 4 motor
ID 7 motor	◀ 7 CABLE-14 ▶	CM-510
ID 8 motor	◀ 8 CABLE-18 ▶	CM-510
ID 9 motor	◀ 9 CABLE-10 ▶	ID 7 motor
ID 10 motor	◀ 10 CABLE-10 ▶	ID 8 motor
ID 11 motor	◀ 11 CABLE-10 ▶	ID 9 motor
ID 12 motor	◀ 12 CABLE-10 ▶	ID 10 motor
ID 13 motor	◀ 13 CABLE-18 ▶	ID 11 motor
ID 14 motor	◀ 14 CABLE-14 ▶	ID 13 motor
ID 15 motor	◀ 15 CABLE-14 ▶	ID 14 motor
IR SENSOR	◀ 16 5P-CABLE 15 ▶	CM-510 PORT 1
CM-510	◀ 17 CABLE-BAT ▶	BAT

This diagram illustrates the assembly of the ROBOTIS iBOT-10 robot. The central component is the iBOT-10 unit, which features a top cover labeled 'OPEN' and the 'ROBOTIS iBOT-10' branding. The assembly process involves attaching various components, numbered 3 through 17, to the main unit. Components 3, 5, and 6 are shown as motor assemblies. Components 7, 9, 10, 11, and 12 are shown as wheel and gear assemblies. Component 4 is a cable that connects to the main unit and a connector labeled 17. Arrows indicate the direction of assembly for the wheels and the connection of the cable.



조립 확인하기

조립이 완료 되었으면 아래의 절차에 따라 조립 상태를 확인합니다.

STEP 1

조립 확인 프로그램 실행하기

로봇을 PLAY 모드에 놓고, D 버튼을 누른 상태에서 START 버튼을 누르면 조립 확인 프로그램이 실행됩니다.

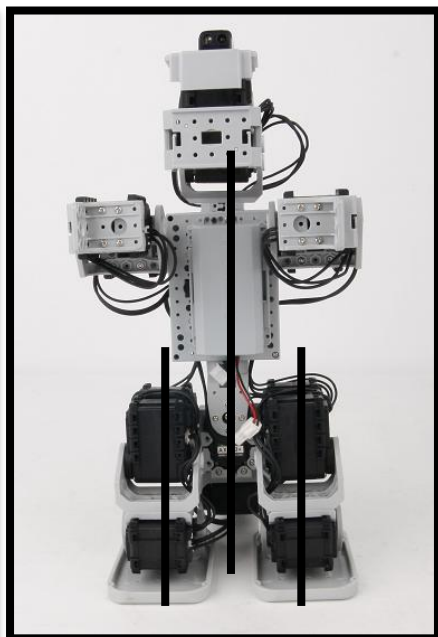
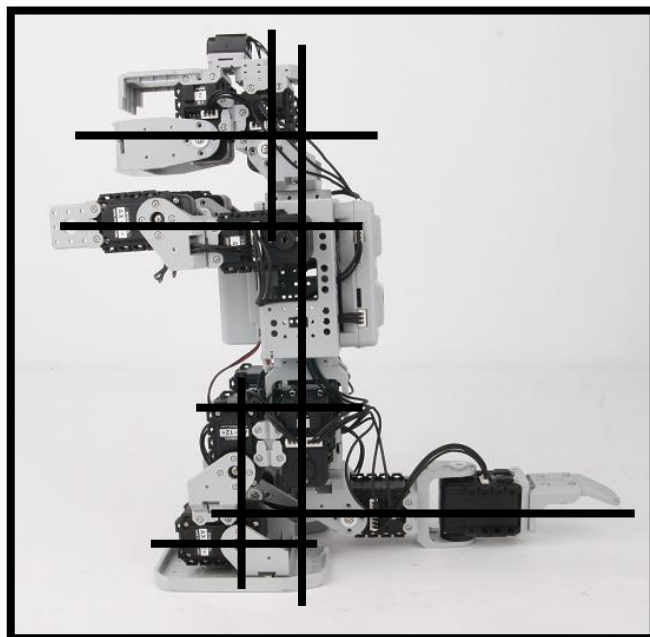
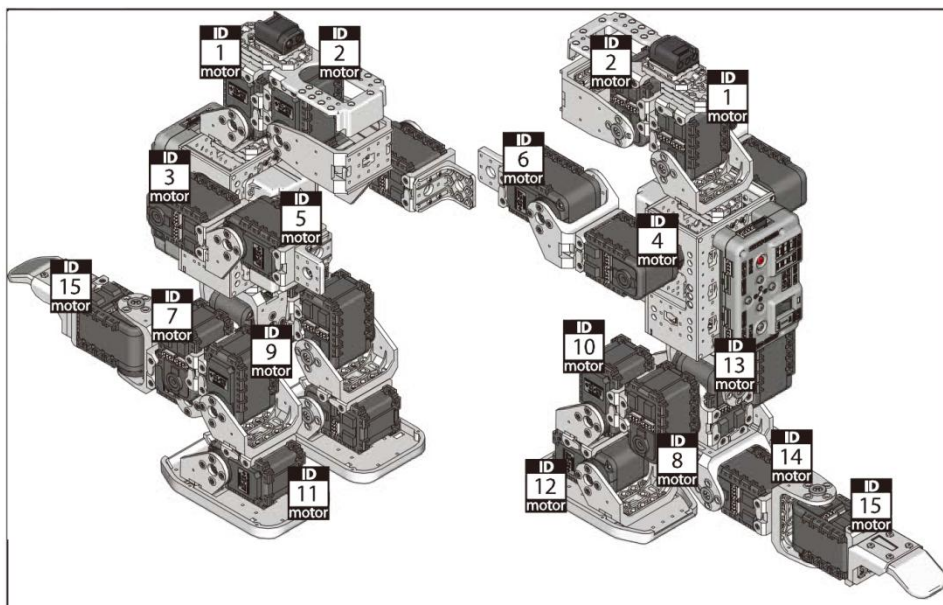
STEP 2

AX12+ 초기위치 및 아이디 확인 모드

모터를 하나씩 선택하여 아래 그림과 비교하세요. U / D 버튼을 눌러 모터를 하나씩 선택합니다. 이 때, 선택된 모터는 LED가 켜지며 초기 위치로 돌아갑니다.

(ID 1번에서 시작, U 버튼 : ID를 1씩 증가시킴. D 버튼 : ID를 1씩 감소시킴)

해당 ID의 모터가 로봇에 존재하지 않을 경우 경고음이 울립니다. LED는 켜져 있지만 모터에 힘이 풀려 있다면, 모터의 조립 상태나 주변의 케이블 등을 다시 살펴보세요.

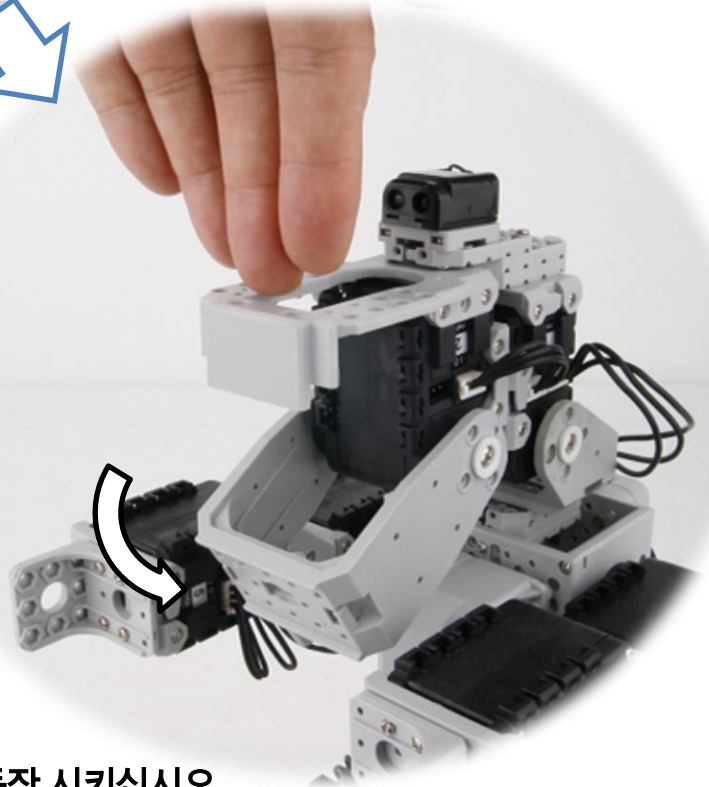
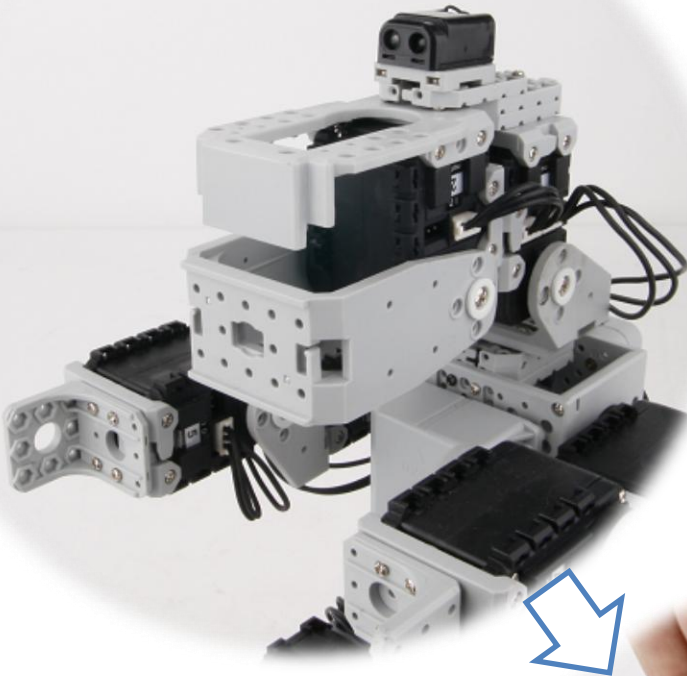


STEP 3

센서 동작 확인 모드

STEP②에서 R 버튼을 누르면 로봇이 전체적으로 초기 위치 즉 위 그림과 같이 됩니다. 위 그림과 다를 경우 모터의 혼과 프레임의 조립상태를 확인하세요. 이 상태에서 각 각의 센서에 손을 가져가면 아래 그림과 같이 동작합니다. 아래 그림과 같이 동작을 하지 않을 경우 센서의 PORT 및 연결 상태를 확인 하세요.

L 버튼을 누르면 로봇이 STEP②로 돌아 갑니다.



STEP 4

이상이 없을 경우 로봇을 동작 시키십시오.

로봇을 PLAY모드에 놓고 START 버튼을 누르면 동작을 시작합니다.