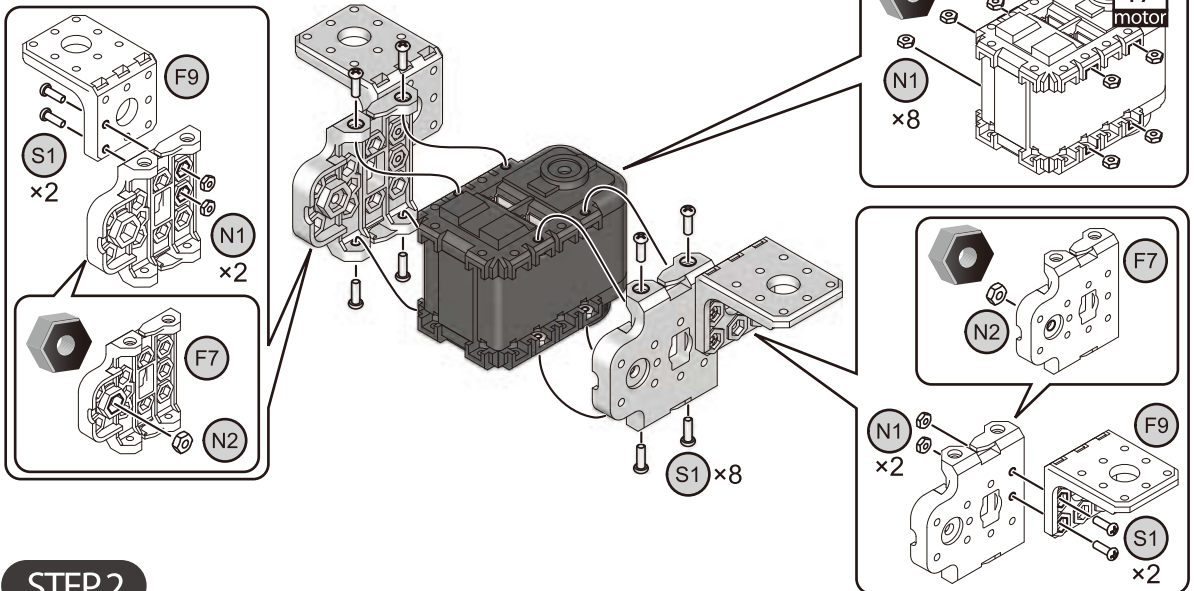


# BIOLOID

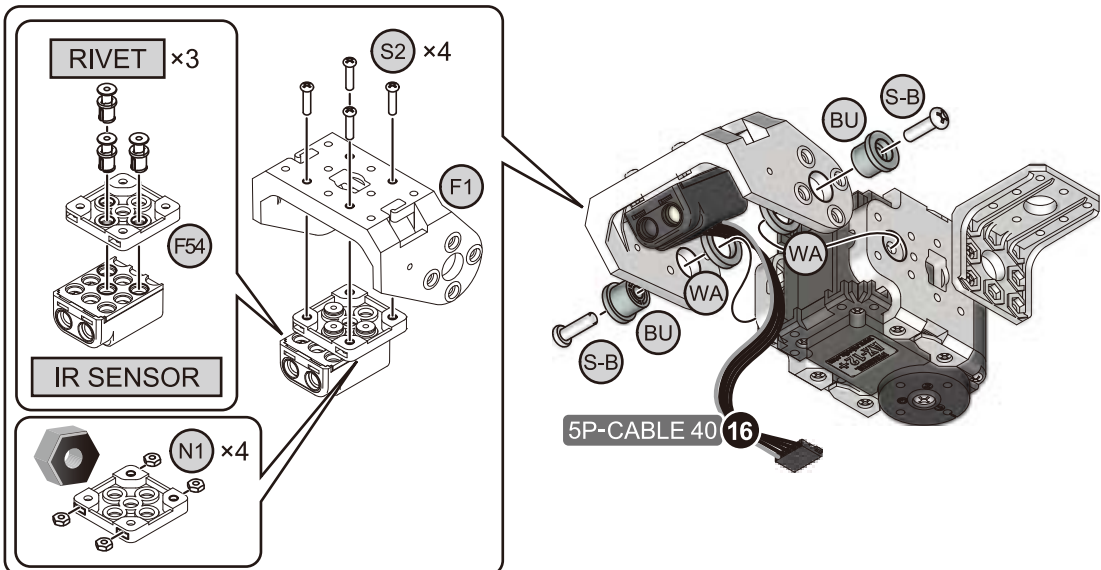
Puppy



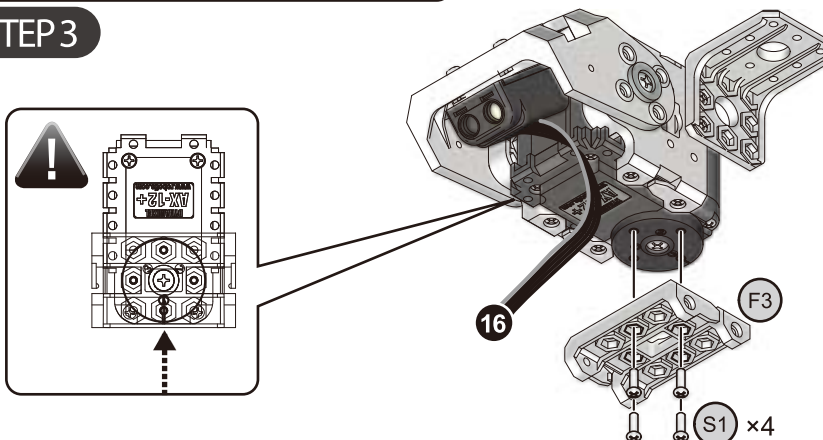
## STEP 1



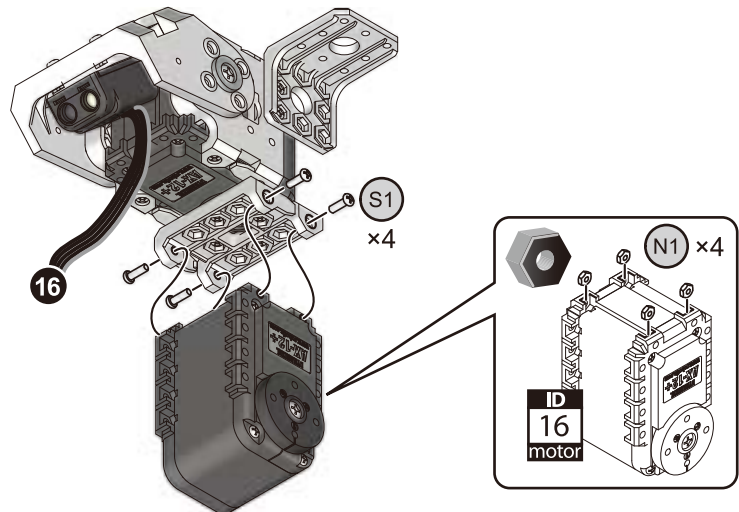
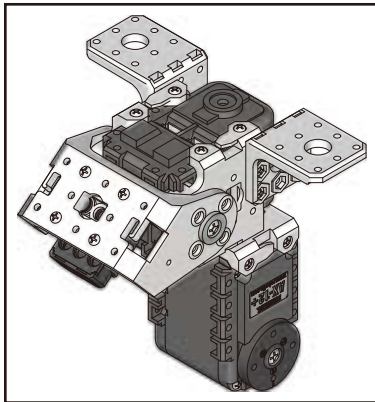
## STEP 2



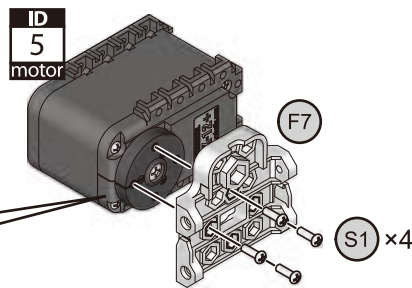
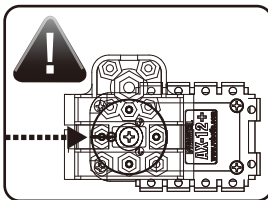
## STEP 3



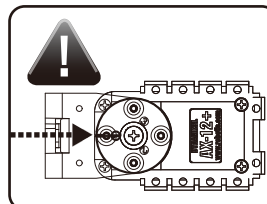
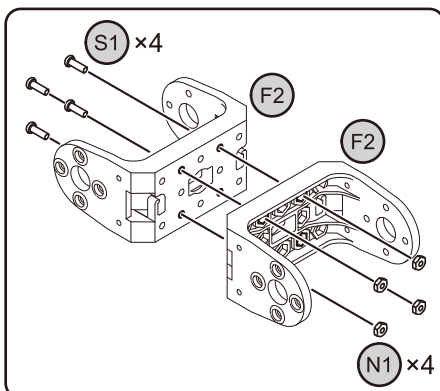
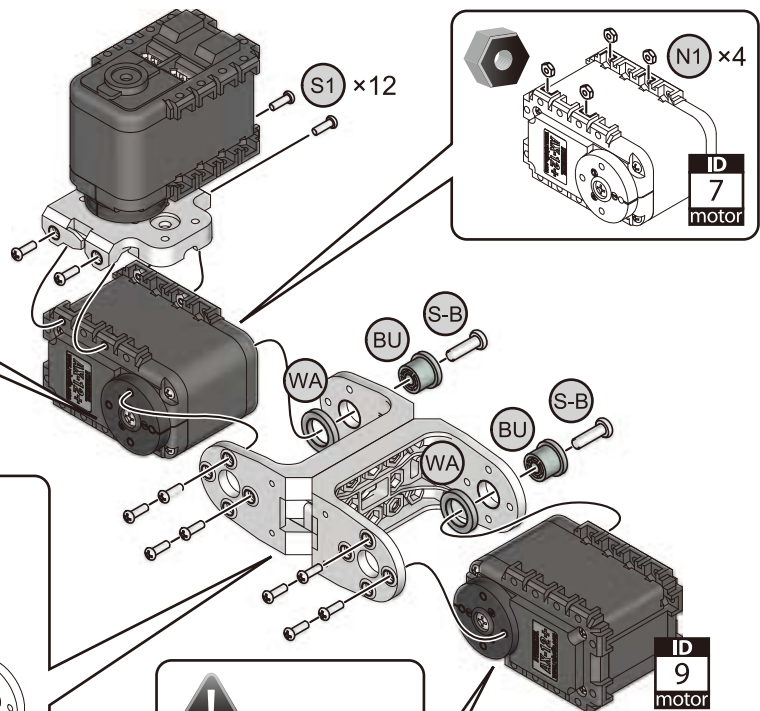
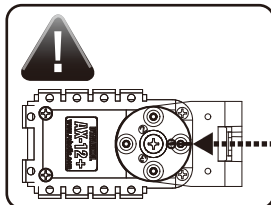
## STEP 4



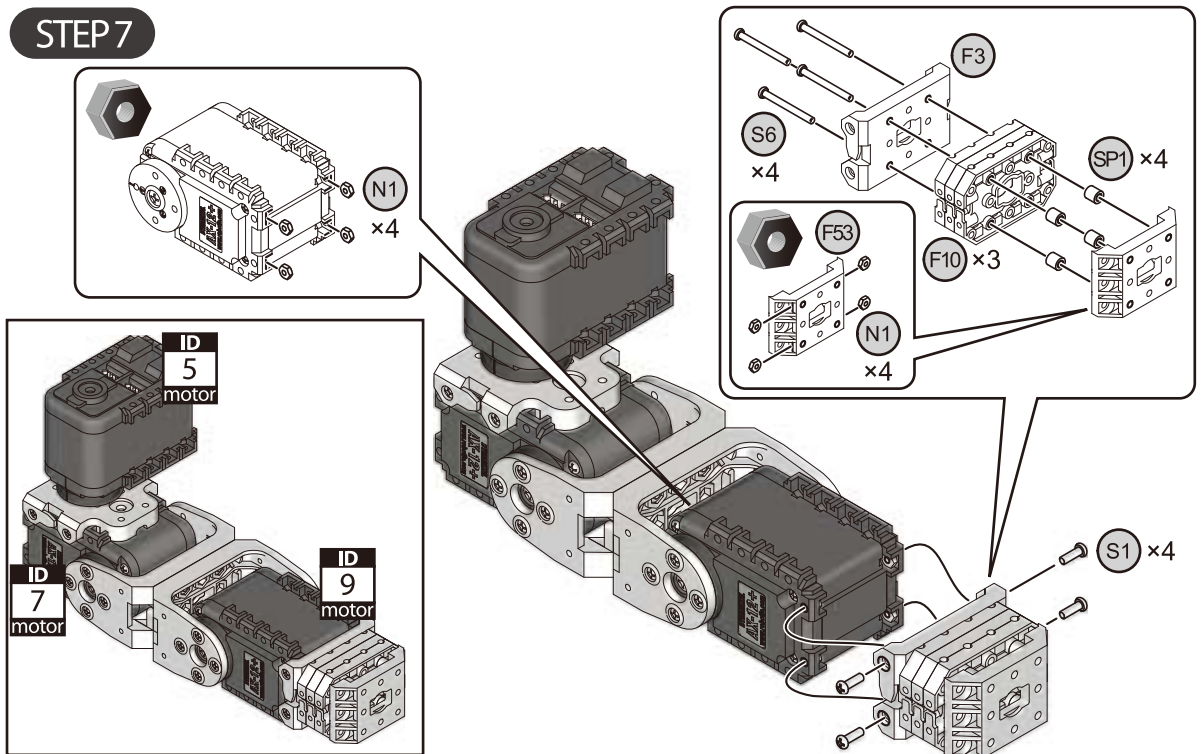
## STEP 5



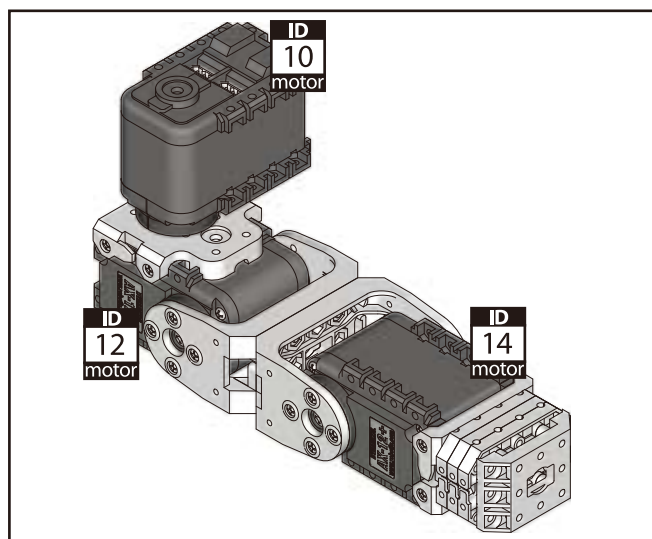
## STEP 6



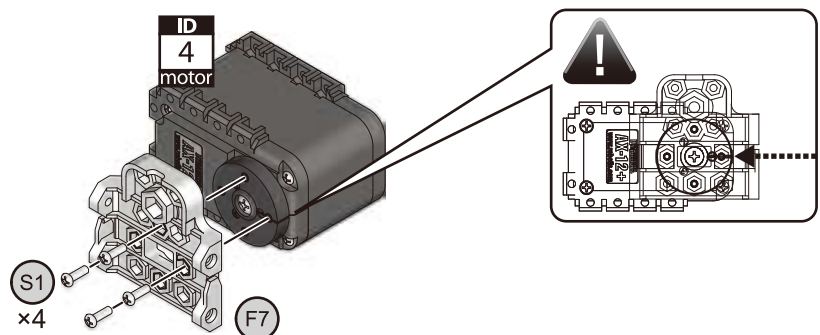
## STEP 7



## STEP 8

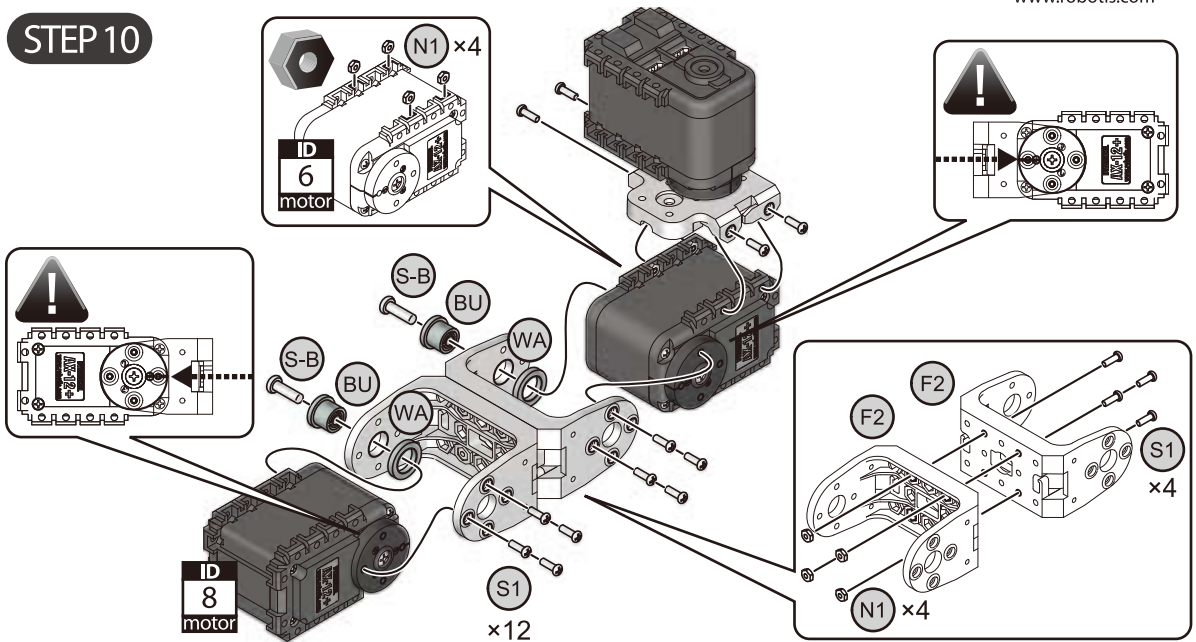


## STEP 9

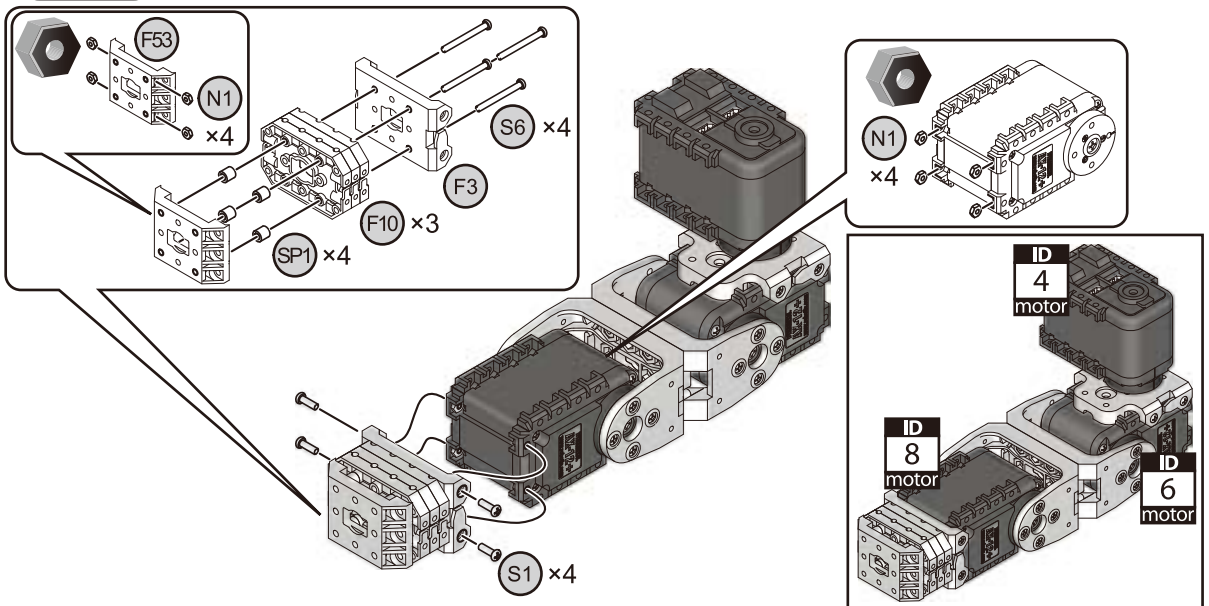




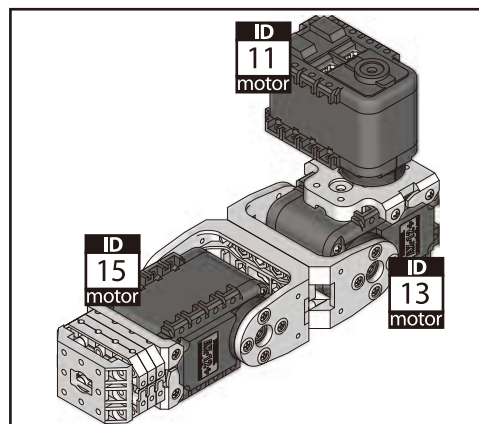
## STEP 10



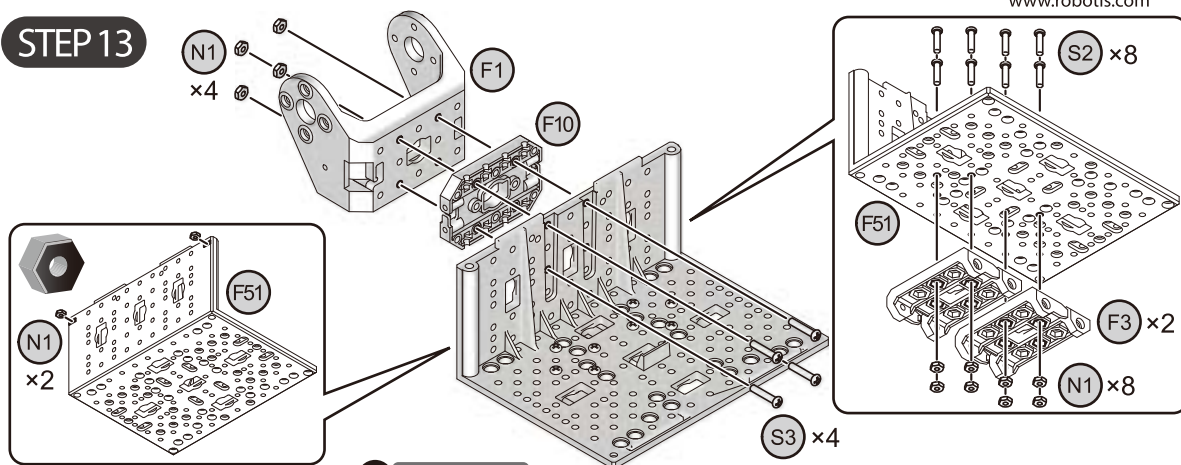
## STEP 11



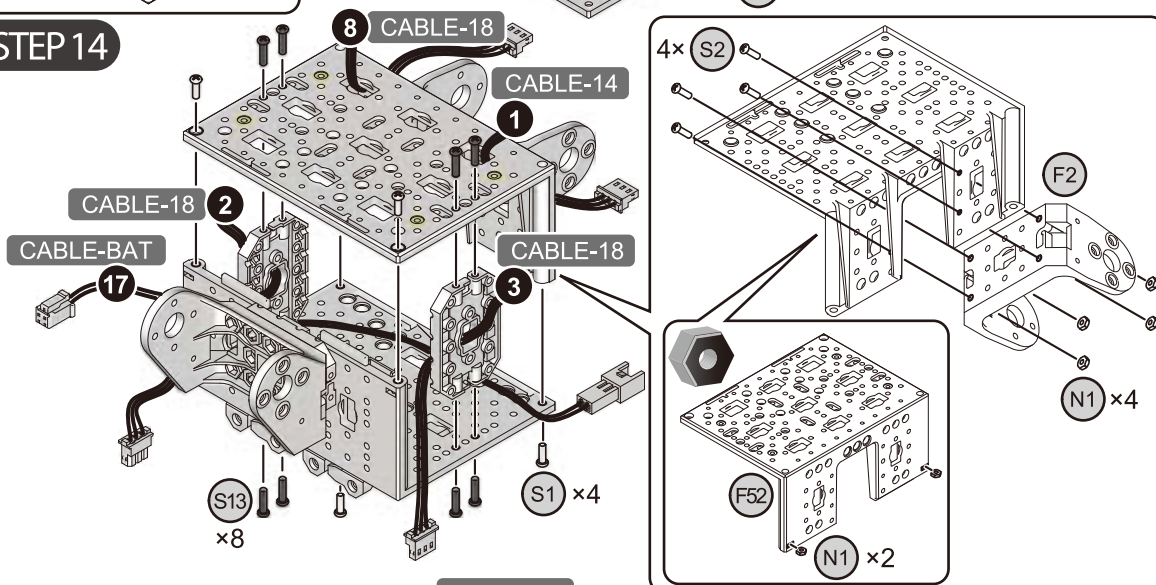
## STEP 12



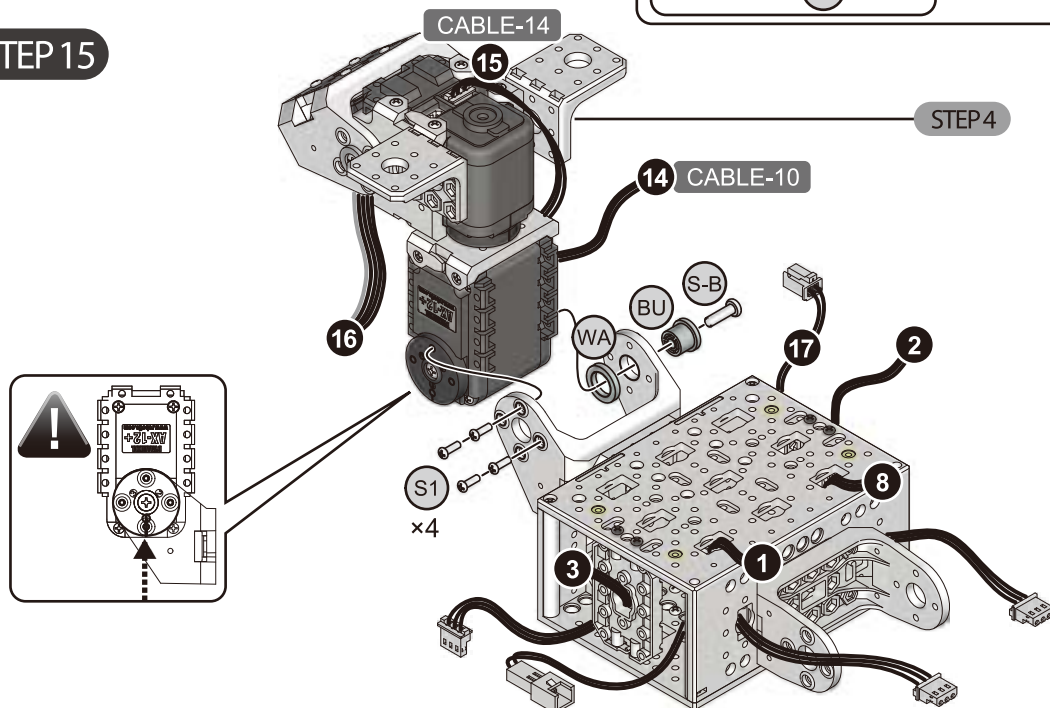
## STEP 13



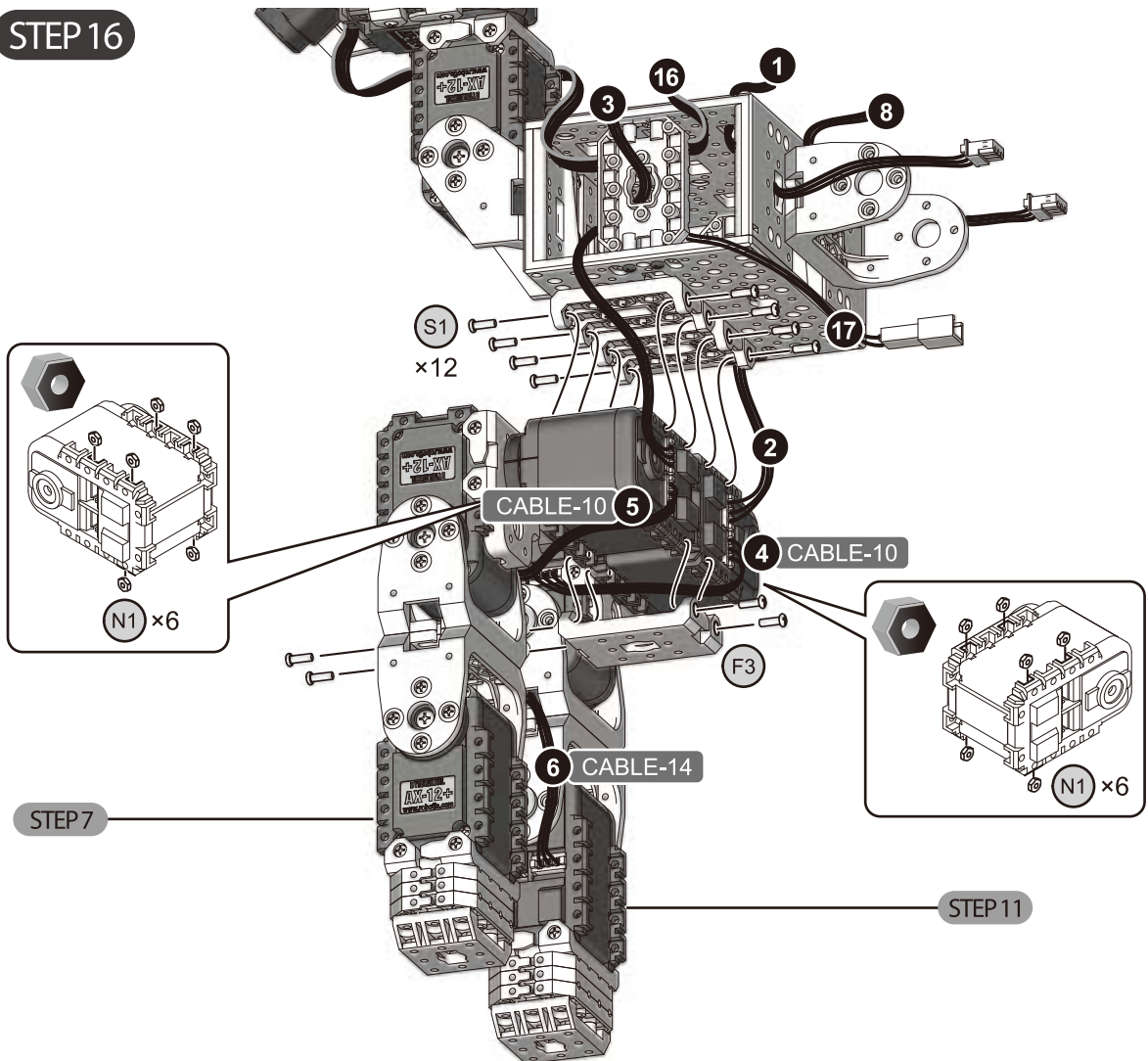
## STEP 14



## STEP 15



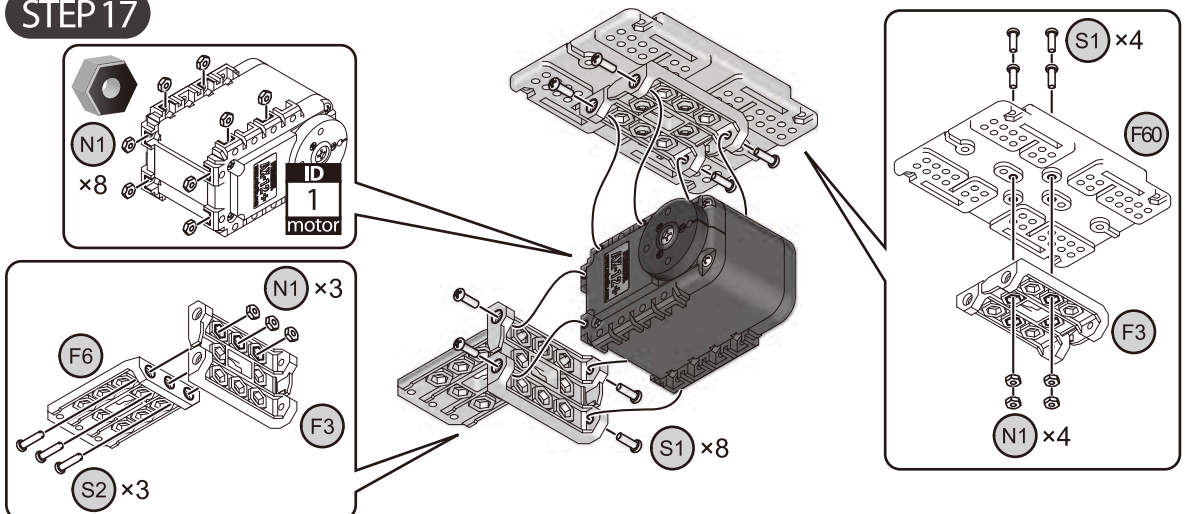
## STEP 16



STEP 7

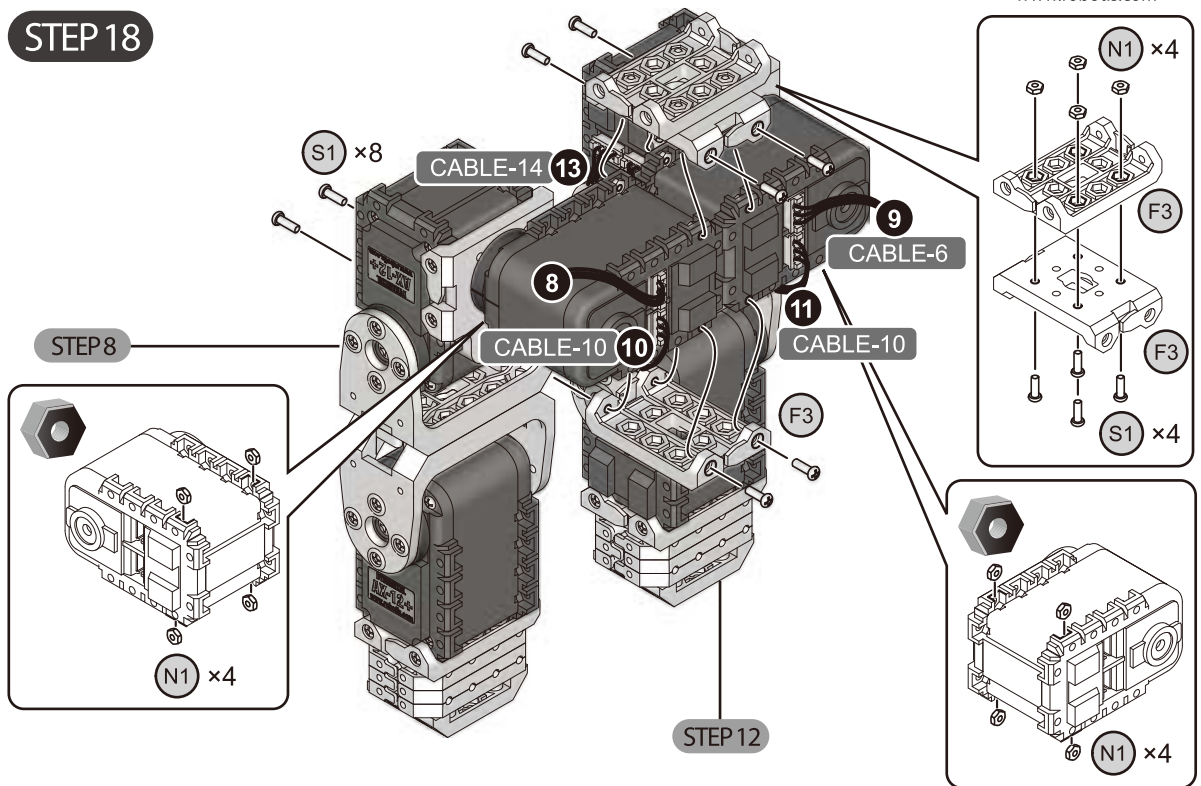
STEP 11

## STEP 17

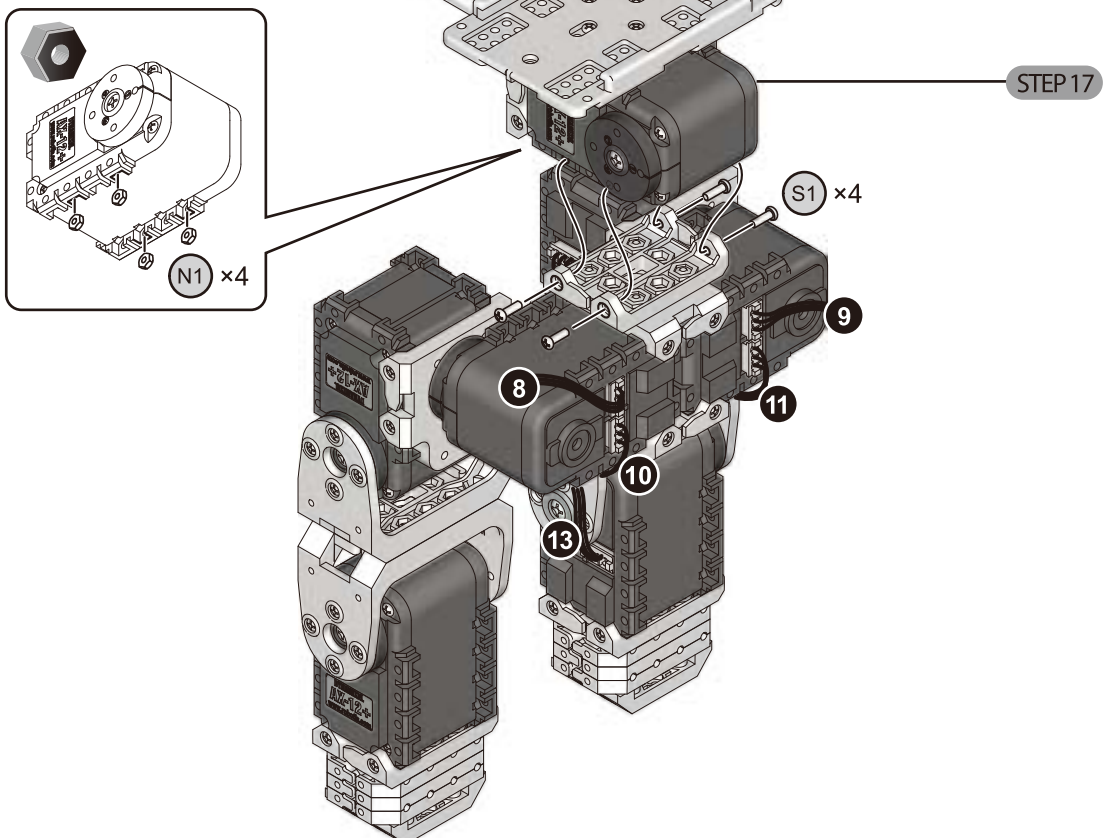




## STEP 18



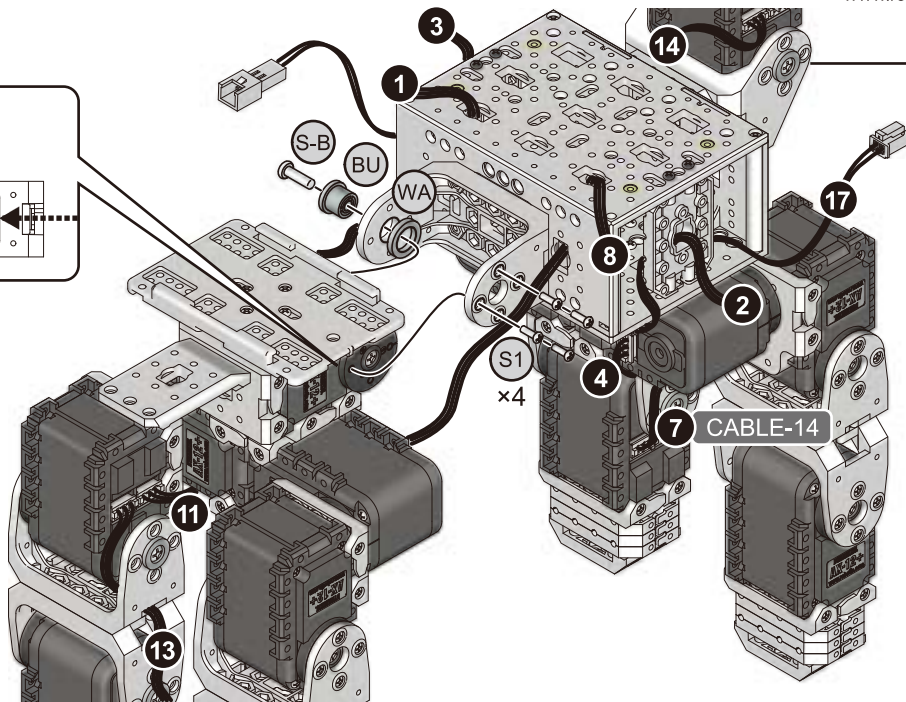
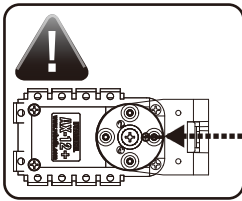
## STEP 19



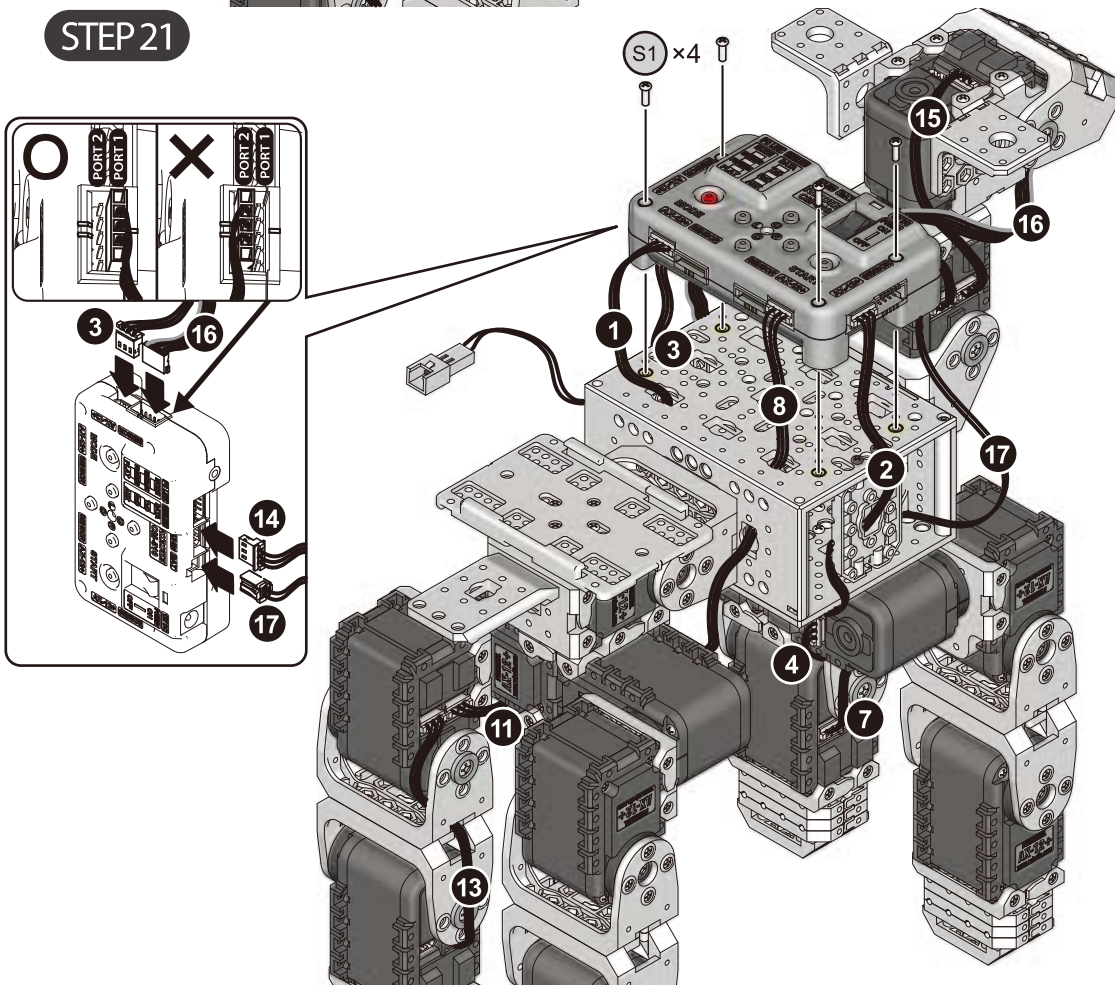
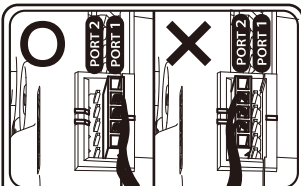


## STEP 20

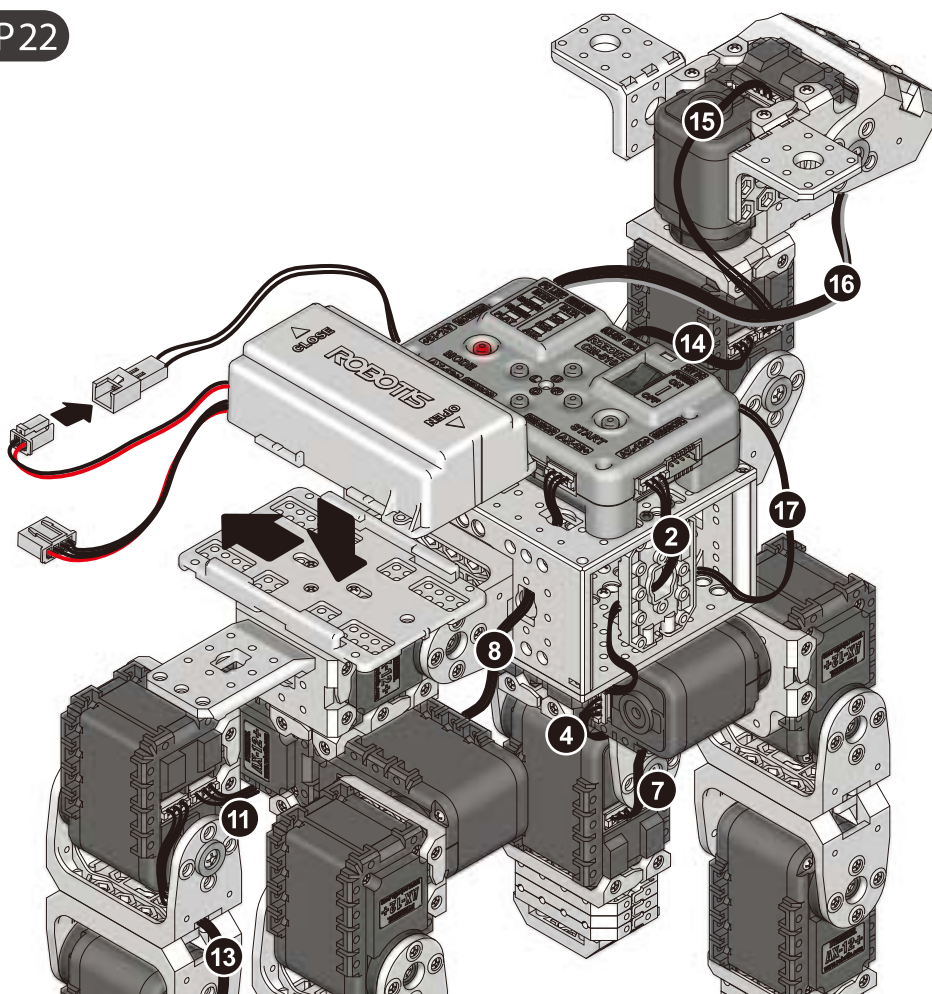
## STEP 18



## STEP 21



## STEP 22



ID 1 motor ◀ 1 CABLE-14 ▶ CM-510

ID 4 motor ◀ 2 CABLE-18 ▶ CM-510

ID 5 motor ◀ 3 CABLE-18 ▶ CM-510

ID 6 motor ◀ 4 CABLE-10 ▶ ID 4 motor

ID 7 motor ◀ 5 CABLE-10 ▶ ID 5 motor

ID 8 motor ◀ 6 CABLE-14 ▶ ID 6 motor

ID 9 motor ◀ 7 CABLE-14 ▶ ID 7 motor

ID 10 motor ◀ 8 CABLE-18 ▶ CM-510

ID 11 motor ◀ 9 CABLE-6 ▶ ID 1 motor

ID 12 motor ◀ 10 CABLE-10 ▶ ID 10 motor

ID 13 motor ◀ 11 CABLE-10 ▶ ID 11 motor

ID 14 motor ◀ 12 CABLE-14 ▶ ID 12 motor

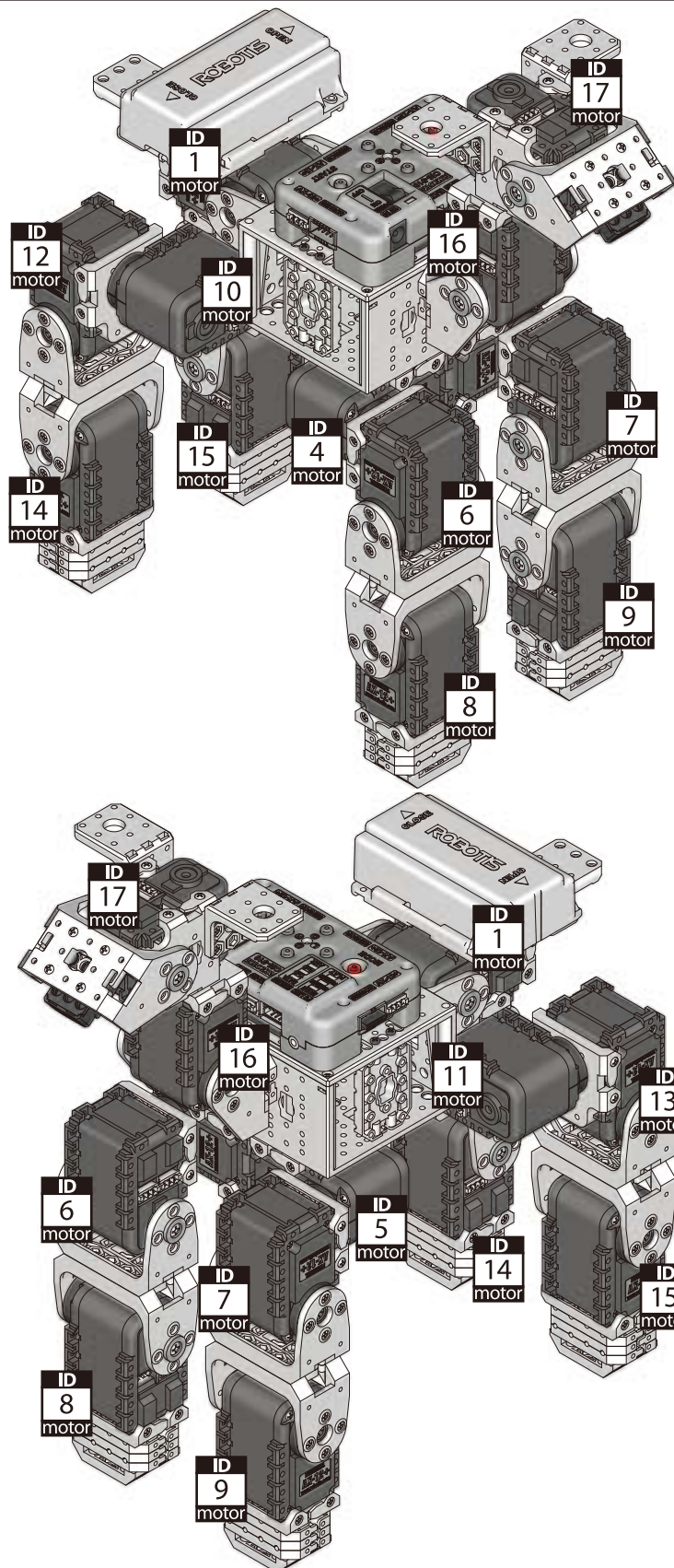
ID 15 motor ◀ 13 CABLE-14 ▶ ID 13 motor

ID 16 motor ◀ 14 CABLE-10 ▶ CM-510

ID 17 motor ◀ 15 CABLE-14 ▶ ID 16 motor

IR SENSOR ◀ 16 5P-CABLE 40 ▶ CM-510 PORT 1

CM-510 ◀ 17 CABLE-BAT ▶ BAT





## 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.

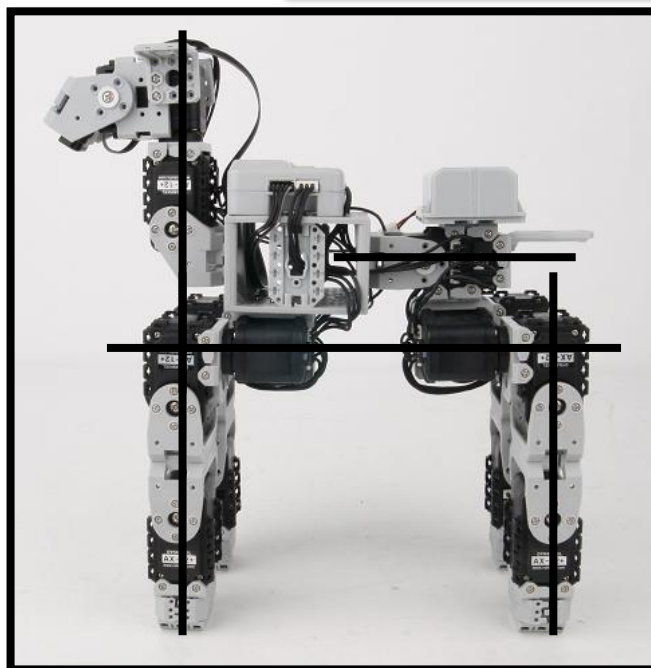
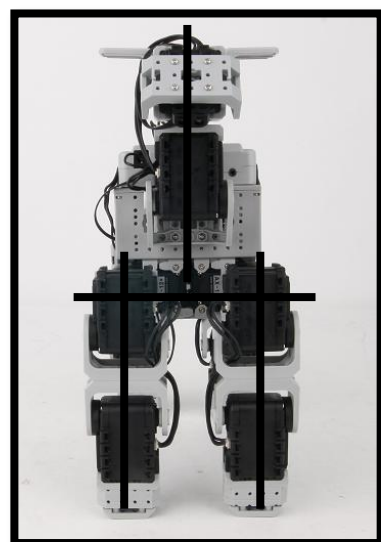
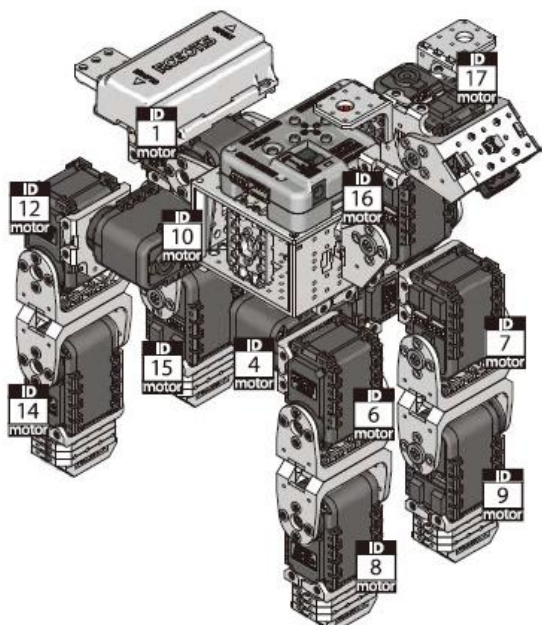
### STEP 2

#### 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.

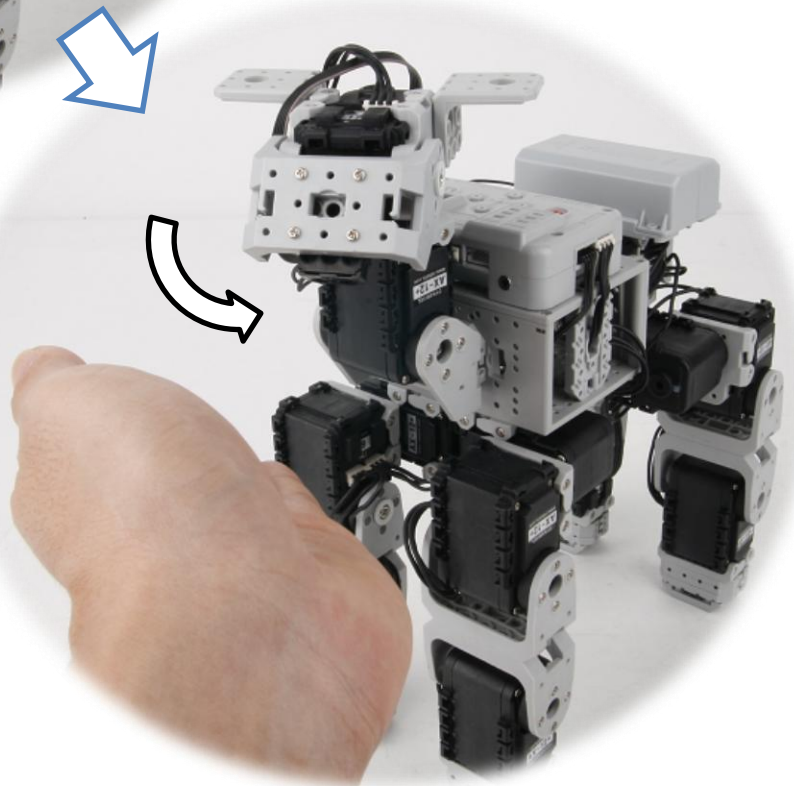
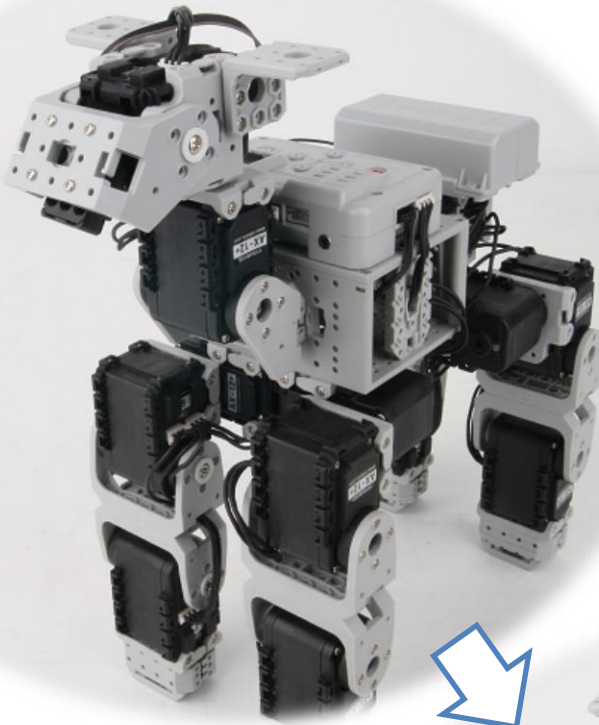


STEP 3

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.