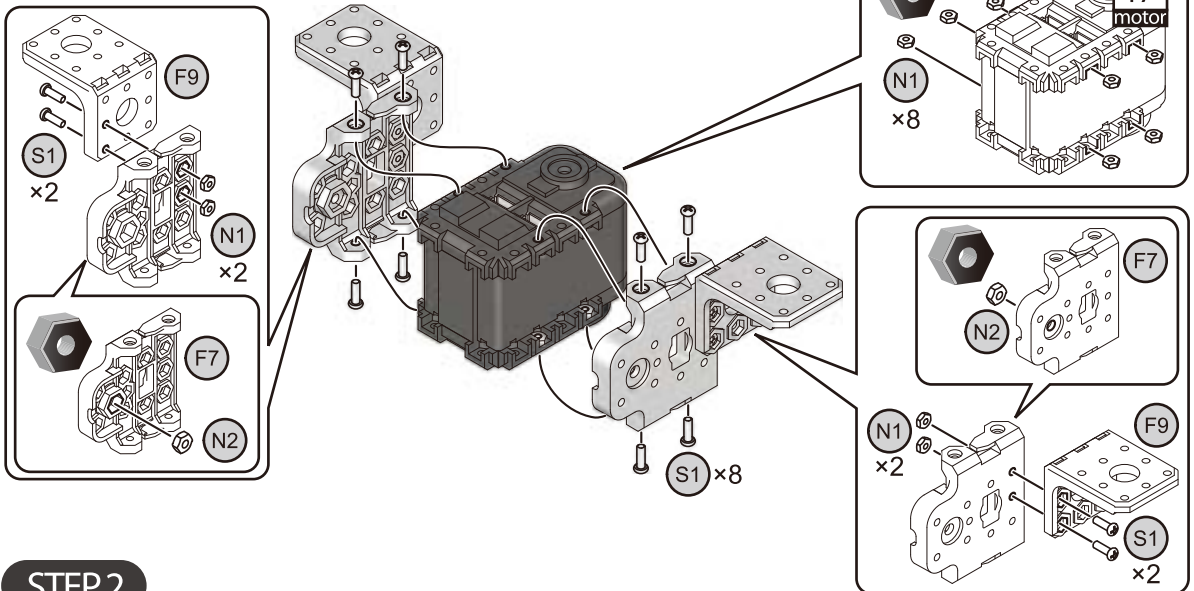


# BIOLOID

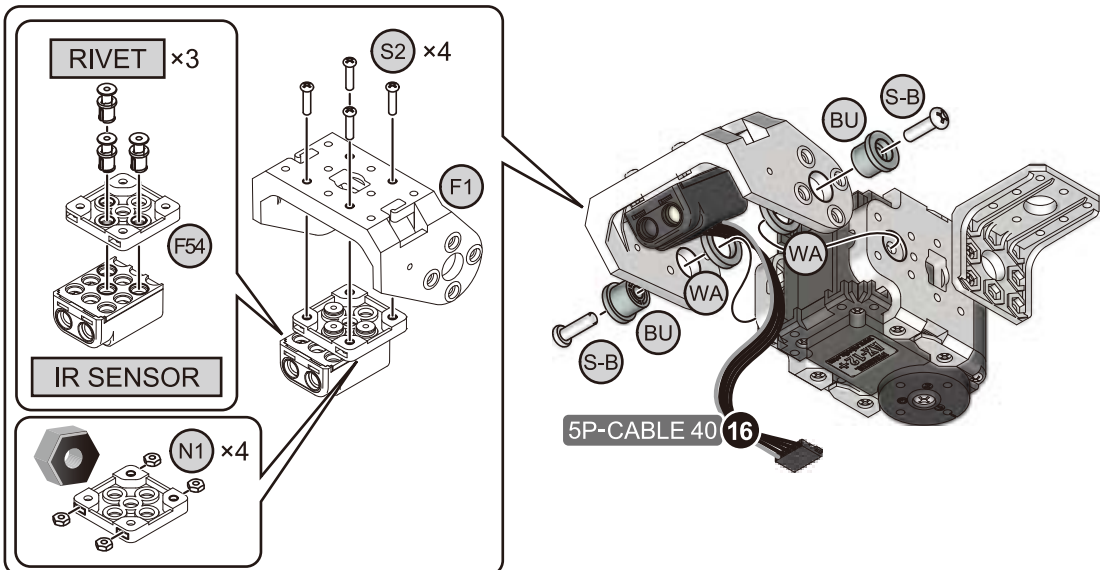
Puppy



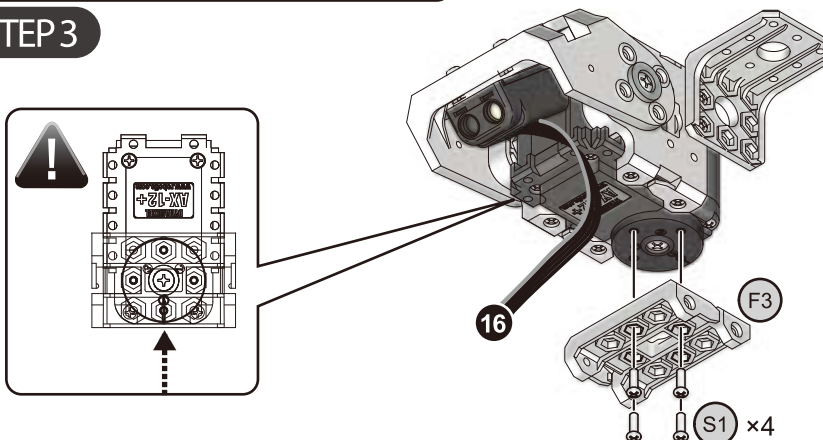
## STEP 1



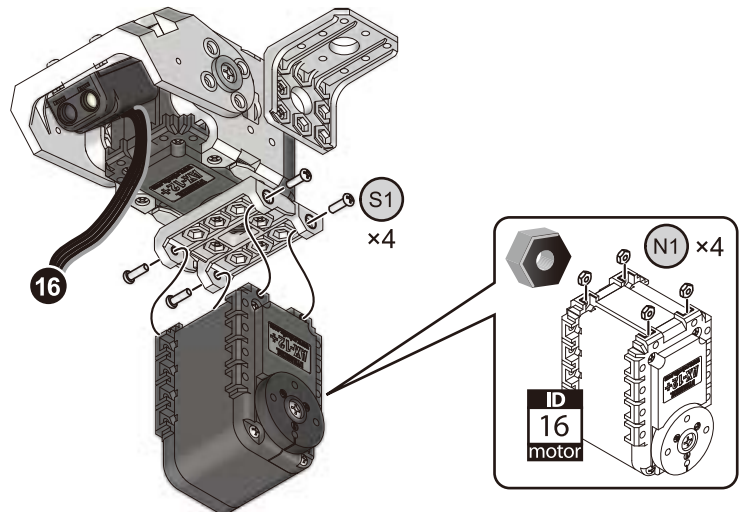
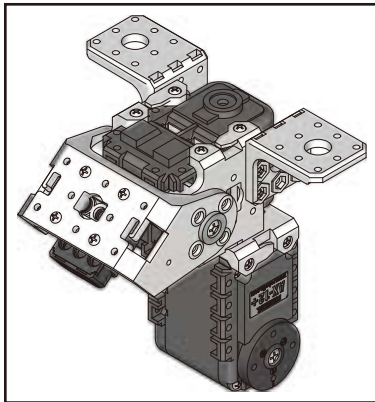
## STEP 2



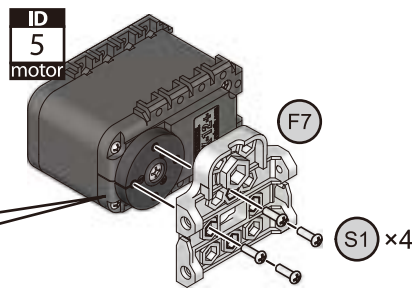
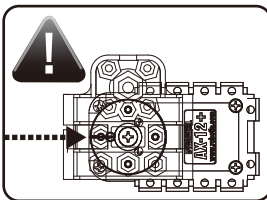
## STEP 3



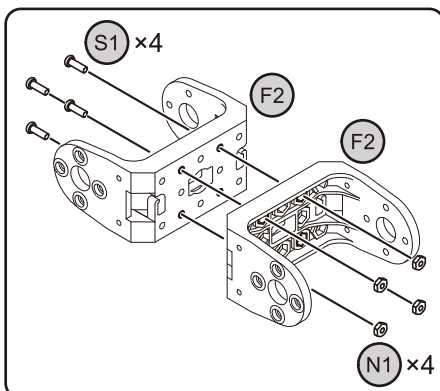
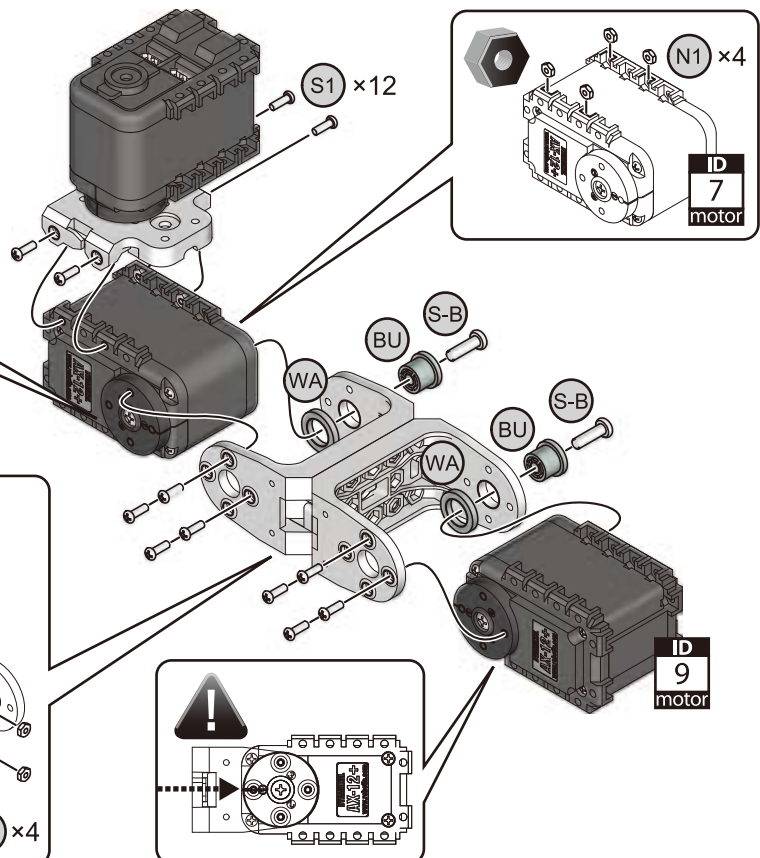
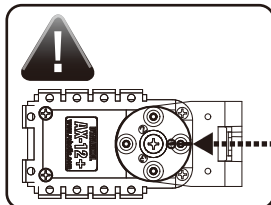
## STEP 4



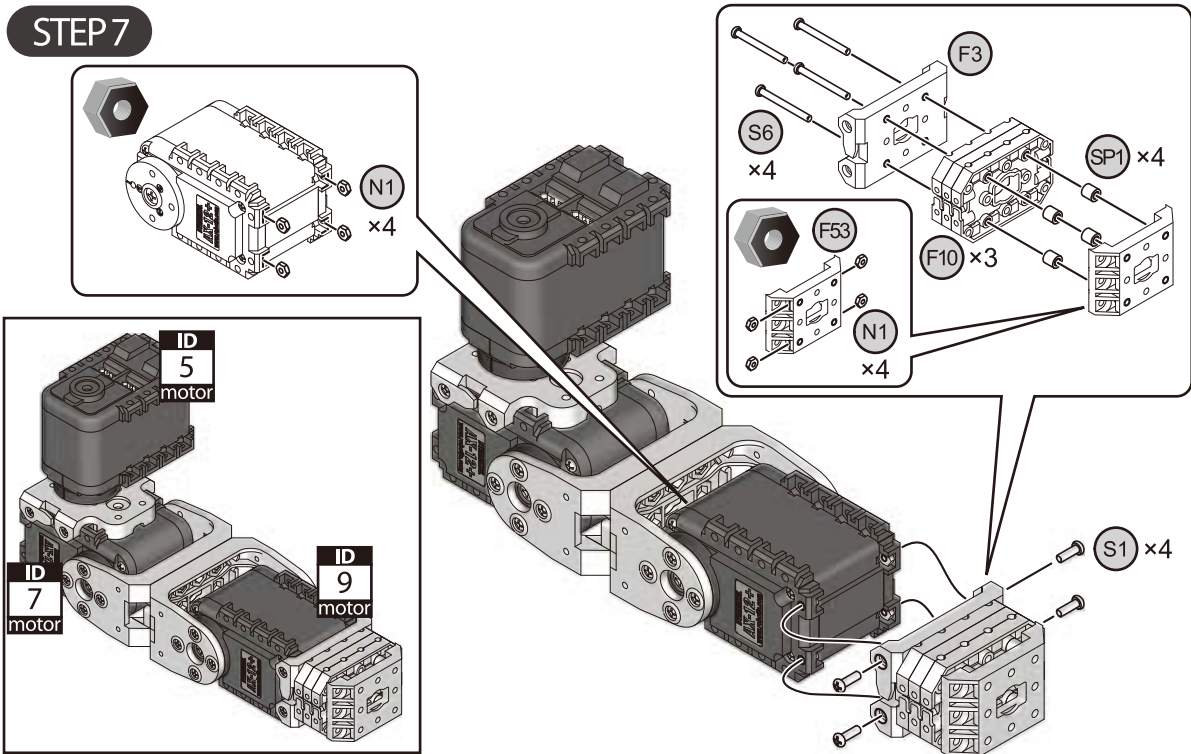
## STEP 5



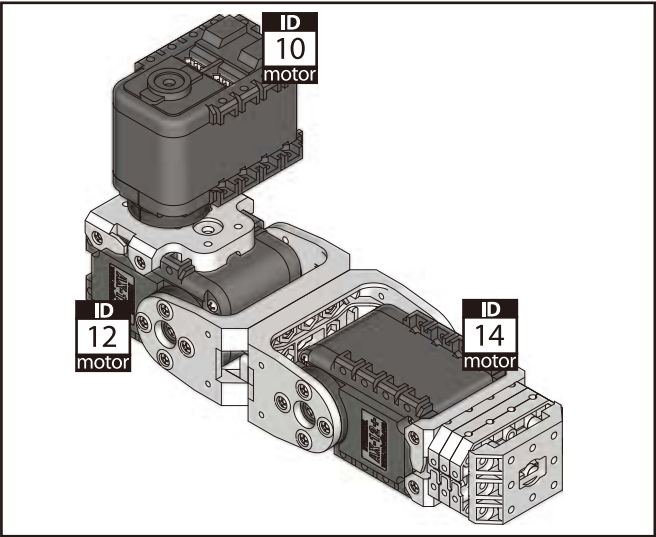
## STEP 6



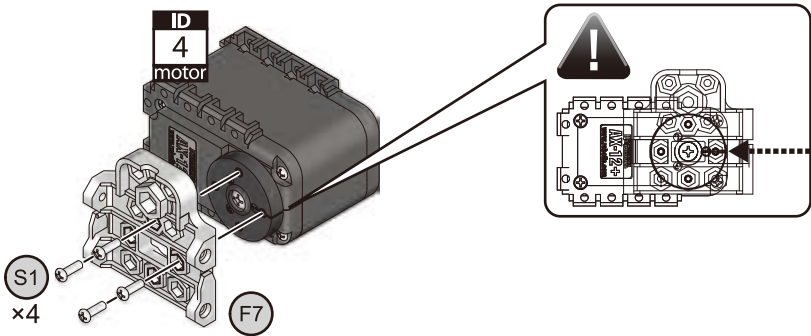
**STEP 7**



**STEP 8**

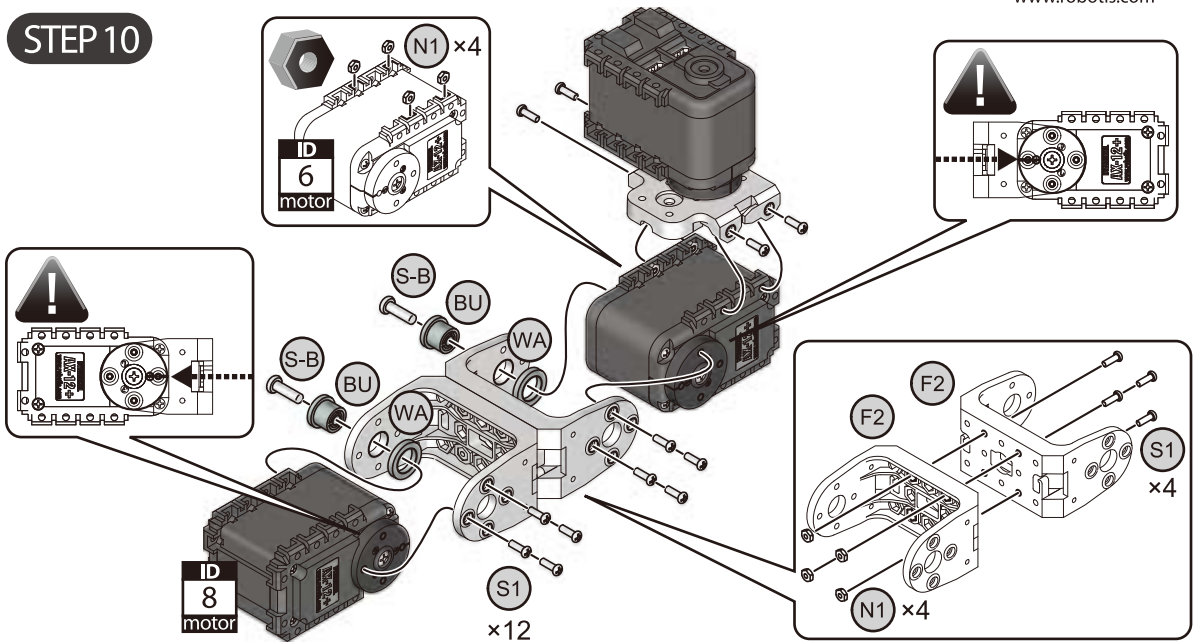


**STEP 9**

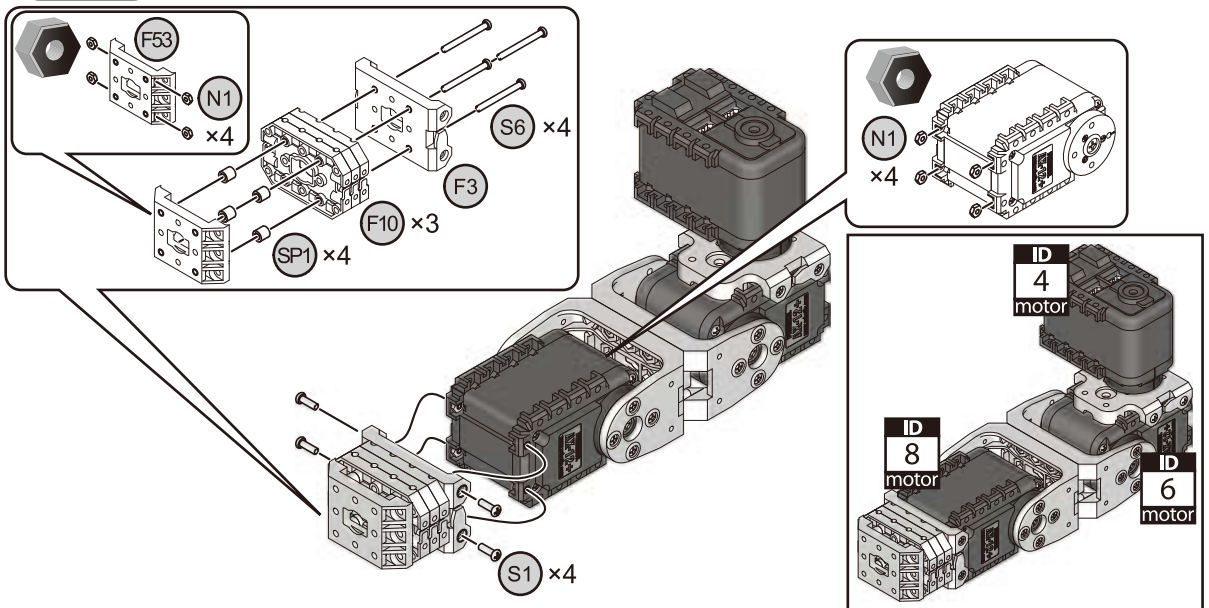




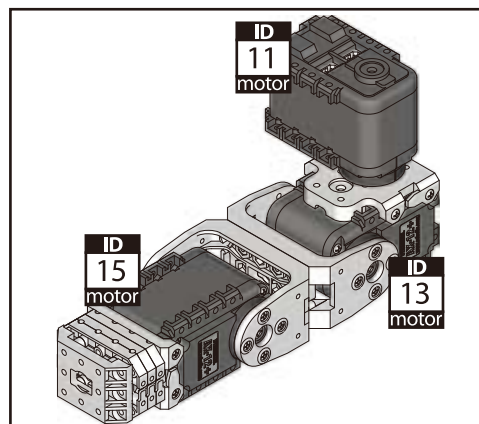
## STEP 10



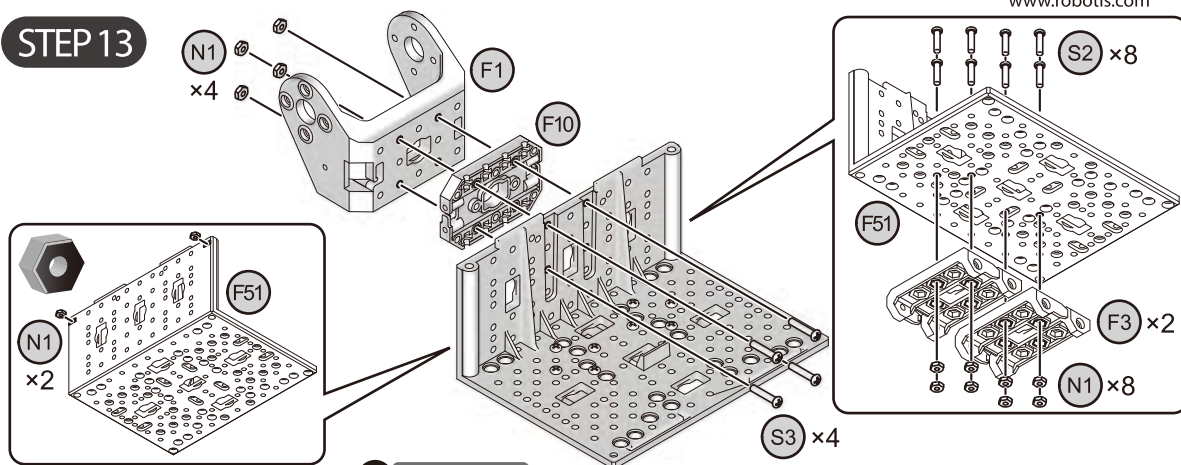
## STEP 11



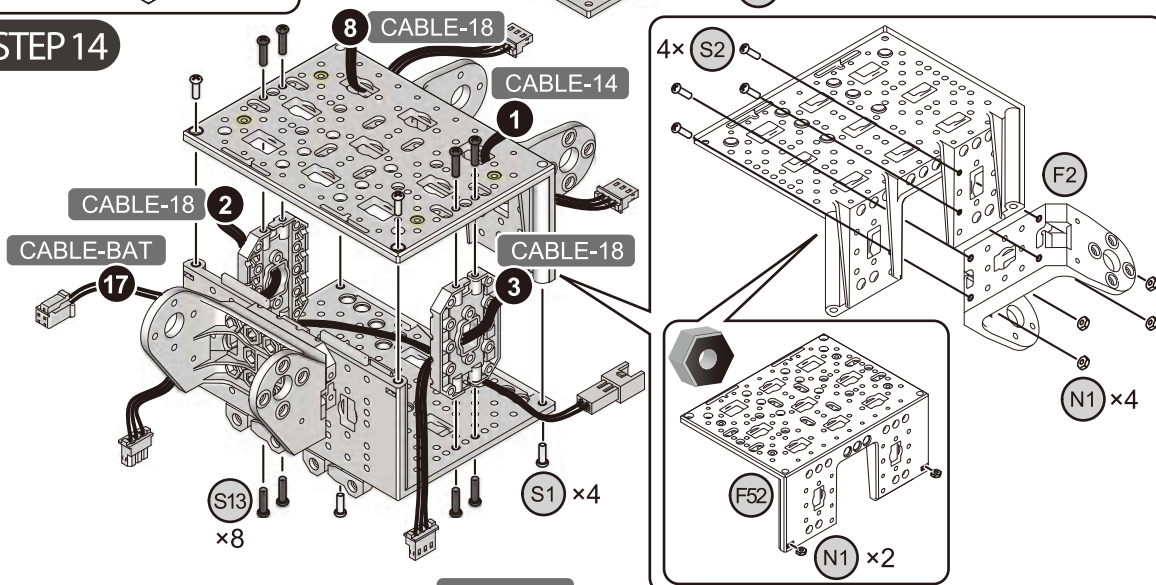
## STEP 12



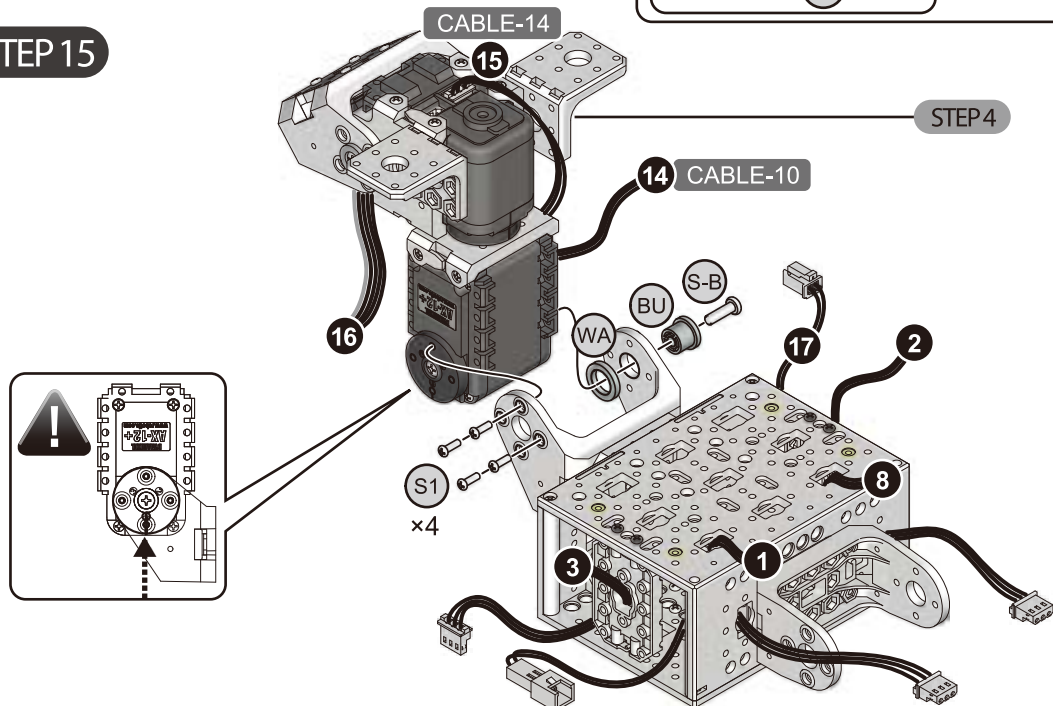
## STEP 13



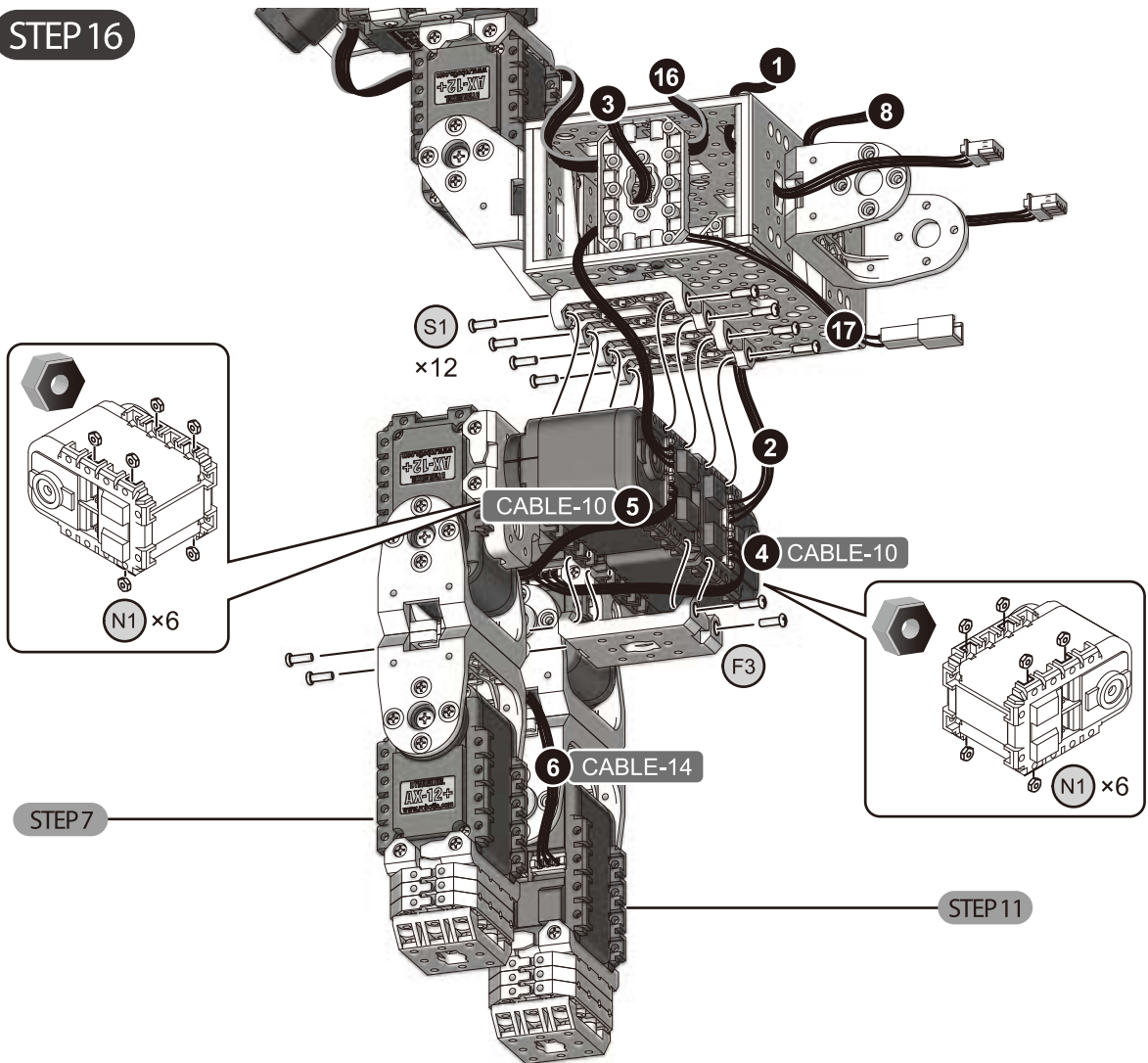
## STEP 14



## STEP 15



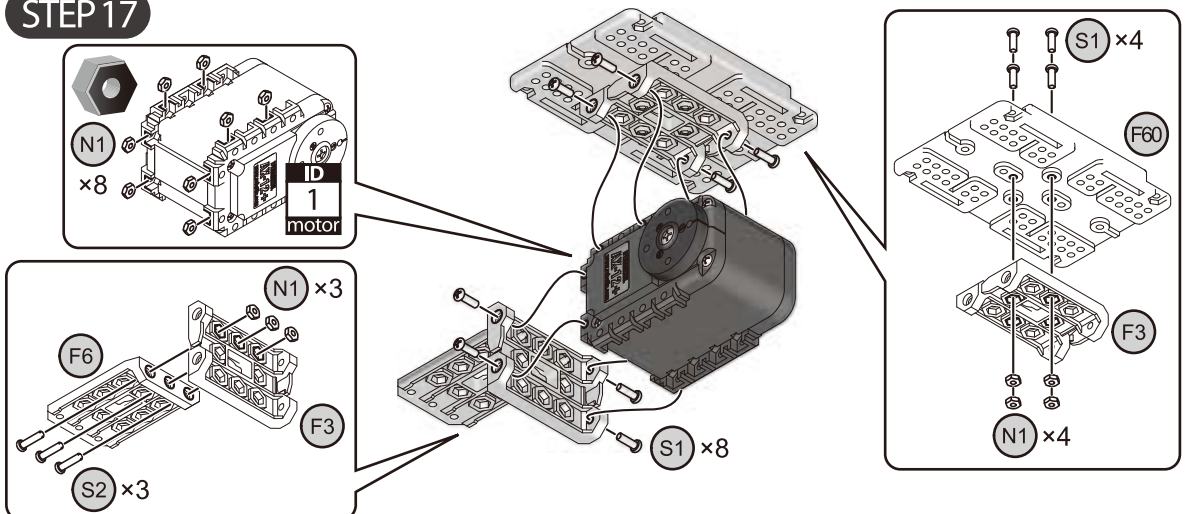
## STEP 16



STEP 7

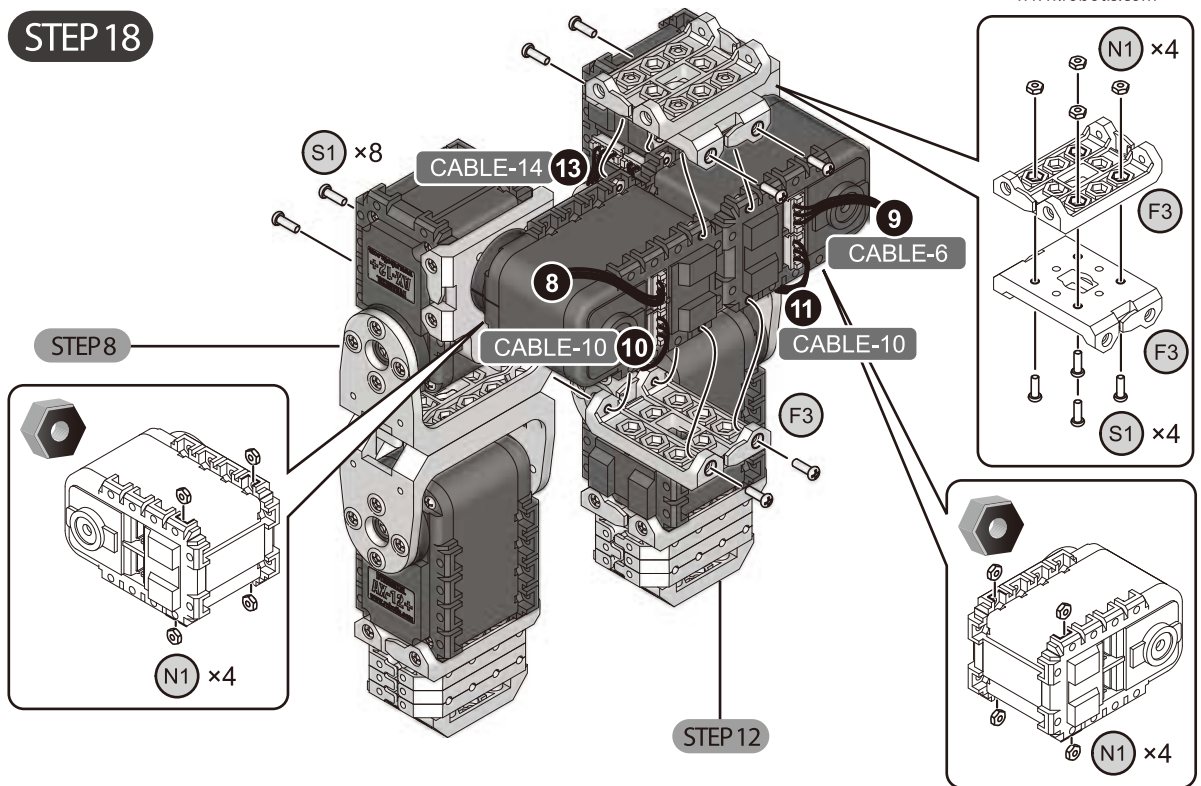
STEP 11

## STEP 17

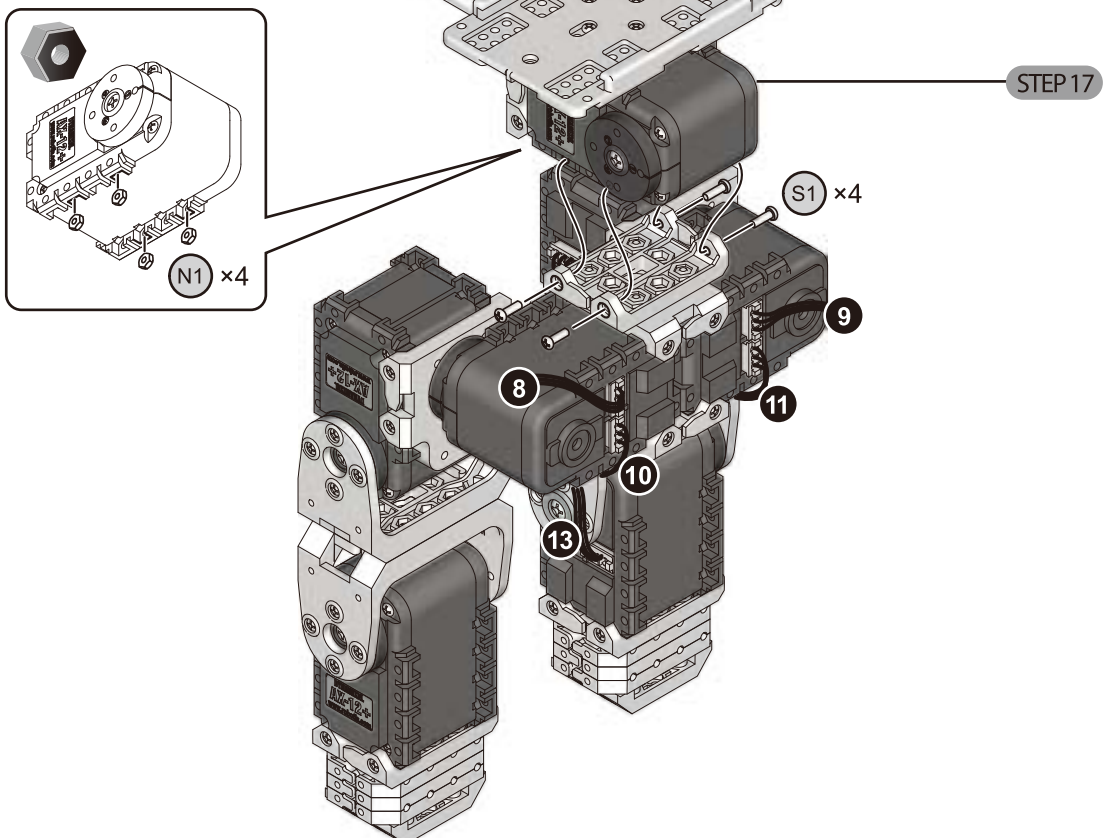




## STEP 18



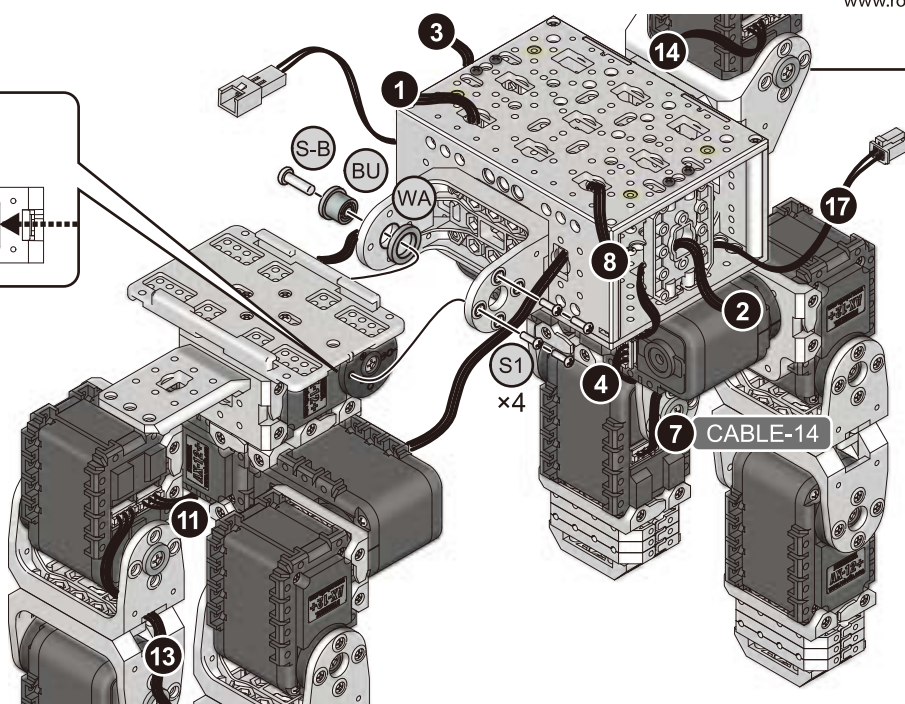
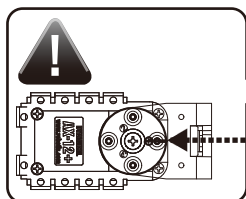
## STEP 19



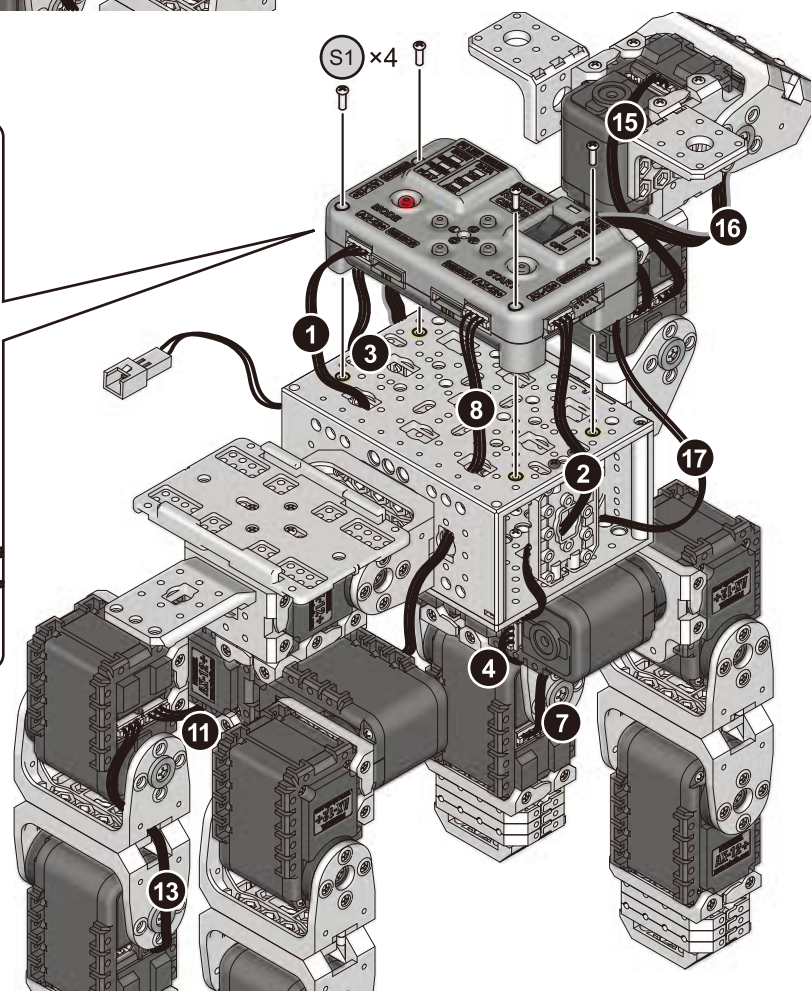


## STEP 20

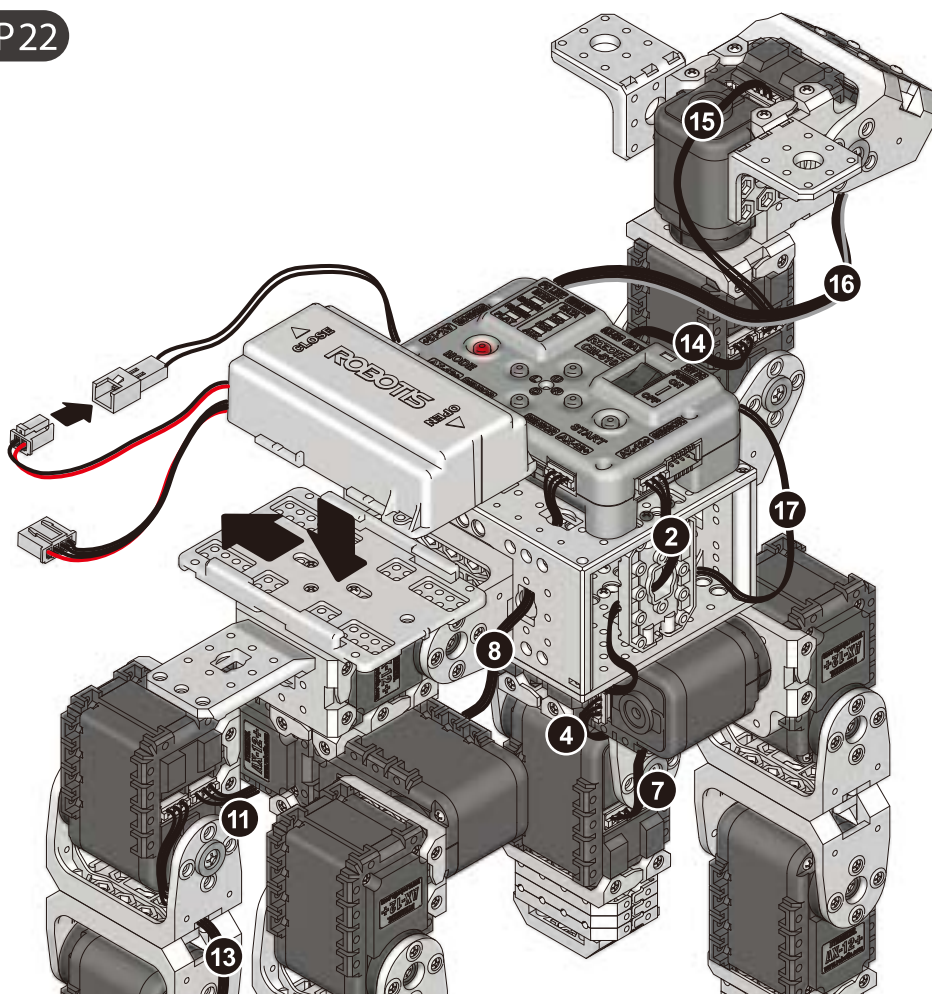
## STEP 18



## 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

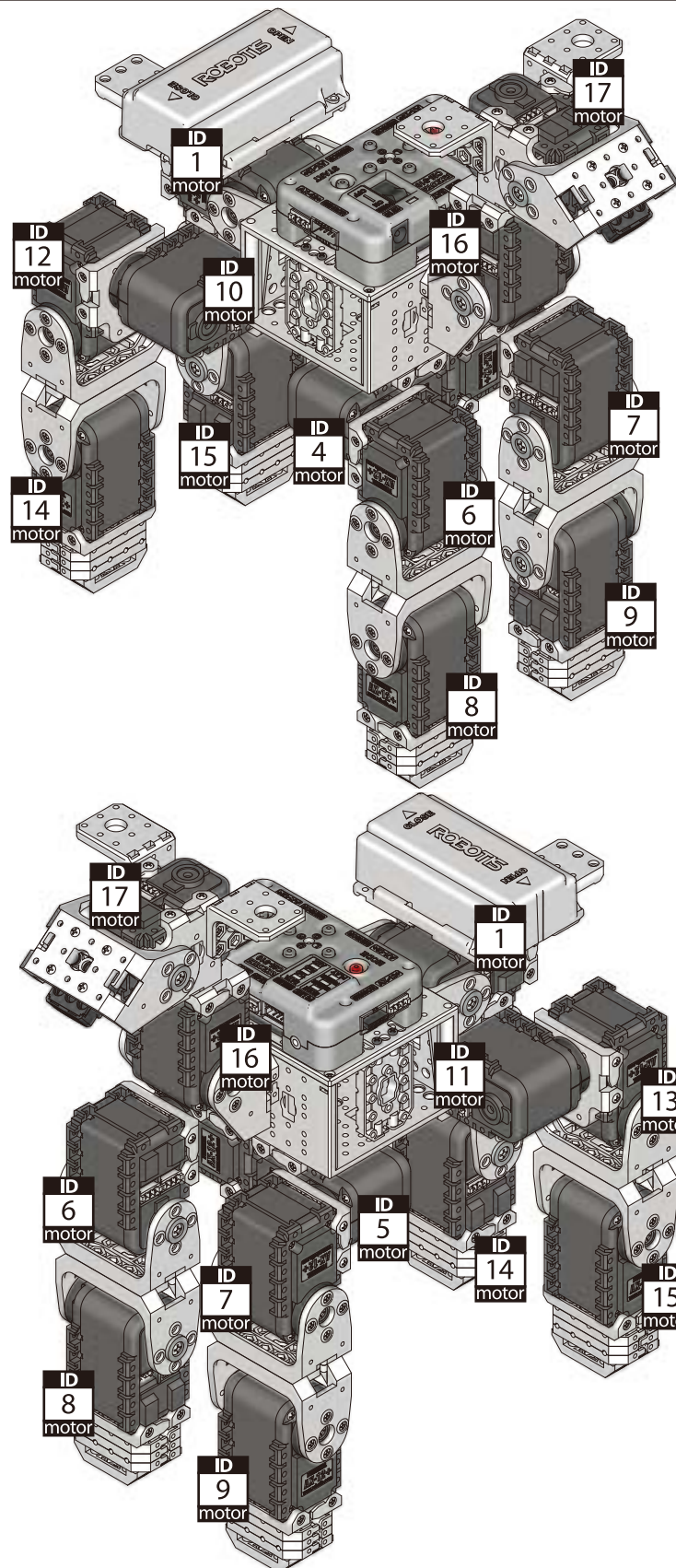
ID 15 motor ◀ 13 CABLE-14 ▶ ID 13 motor

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





## Assembly Check

After assembly please check the following procedure to ensure correctness.

### STEP 1

#### Run the assembly check program

Set the robot in **PLAY** mode; hold the **D** button then press **START**.

Once the **START** button is pressed, the assembly check program begins.

### STEP 2

#### AX12+ initial position and ID check

Select each actuator separately and compare it to the picture below.

Ensure the actuators' horns are properly aligned (the horn's notch should be aligned with the actuator's).

Pressing the **U** or **D** button selects one actuator at a time.

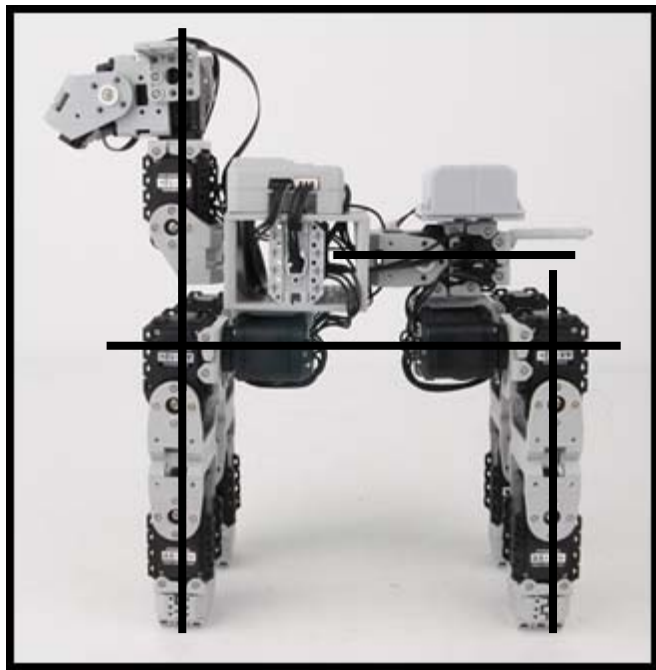
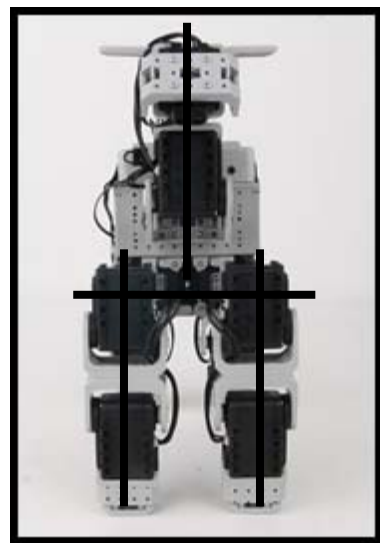
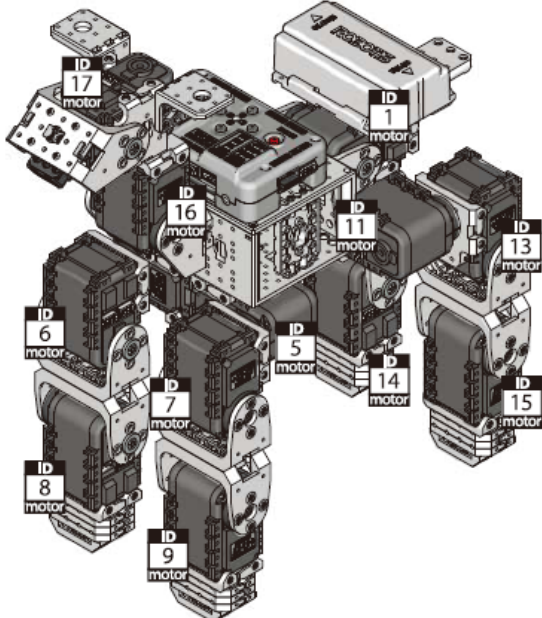
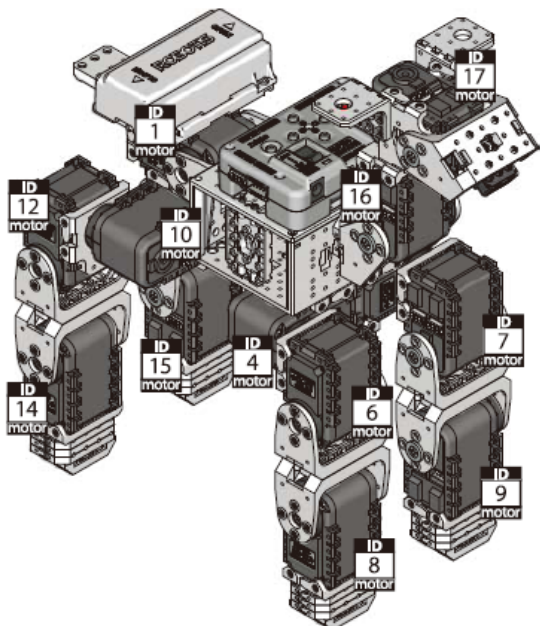
The selected actuator's LED lights up and goes to its initial position.

Check starts from ID1.

**U** moves to the next ID in ascending numerical order; **D**, in descending numerical order.

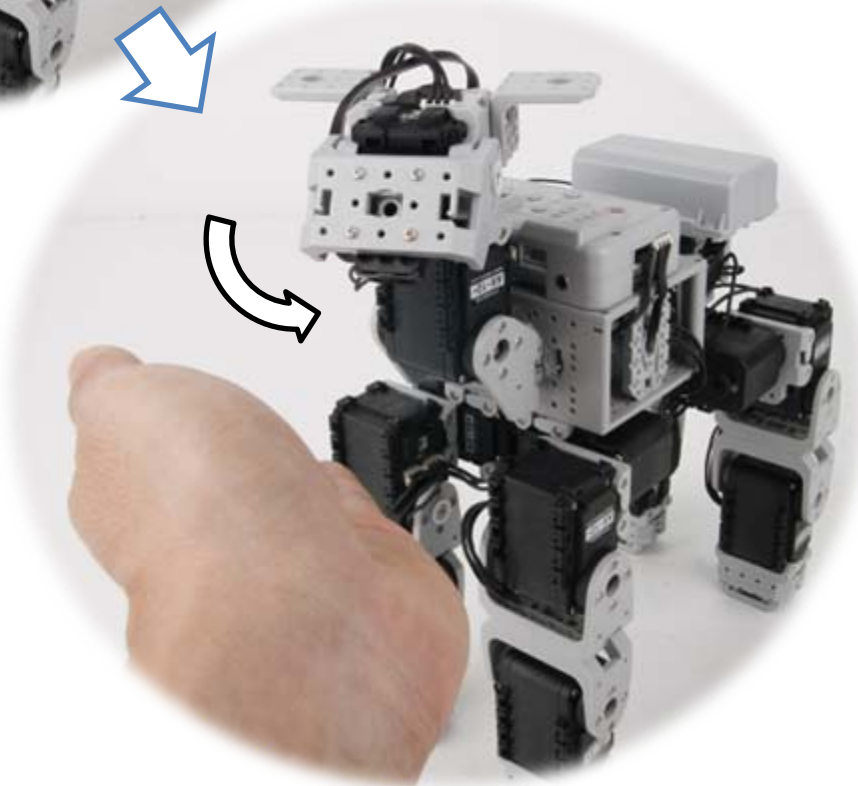
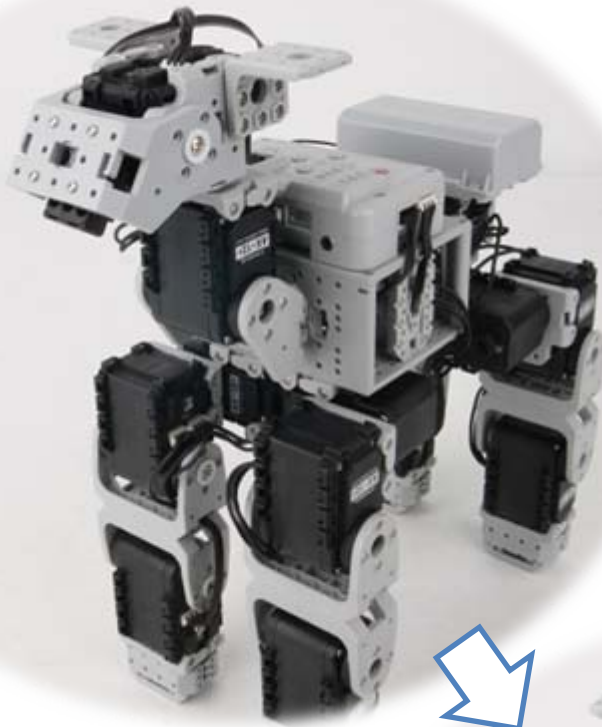
If the actuator's ID does not exist then the robot beeps.

Although the LED may lit, if there is no power then check the wiring on the actuator.



**STEP 3**
**Sensor and behavior check**

From STEP② press **R**. The robot returns to its initial position as pictured above. Place your hand close to the sensors, as pictured below. Robot behavior begins. If the robot does not behave, as pictured below, then check the sensor wiring and its port. Pressing **L** will return the robot back to STEP②.


**STEP 4**
**If everything works fine, play the robot.**

Set the robot in **PLAY** mode. Press **START** and the robot will play.