






Making a Ladybird robot

1

-  X 2
-  X 1
-  X 2
-  (L) X 2
-  X 2



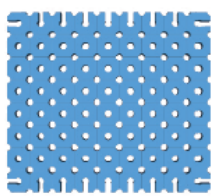


(S) : short
(M) : middle
(L) : long

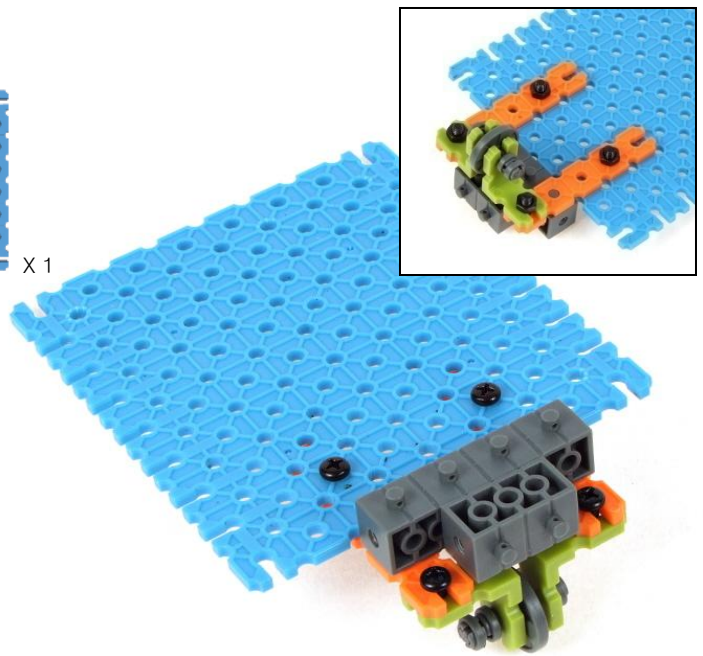
2

-  X 1
-  X 1
-  X 2
-  X 1

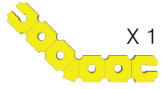


3

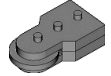
-  X 1
-  (L) X 2
-  X 2



4



X 1



Touch sensor X 1



X 2



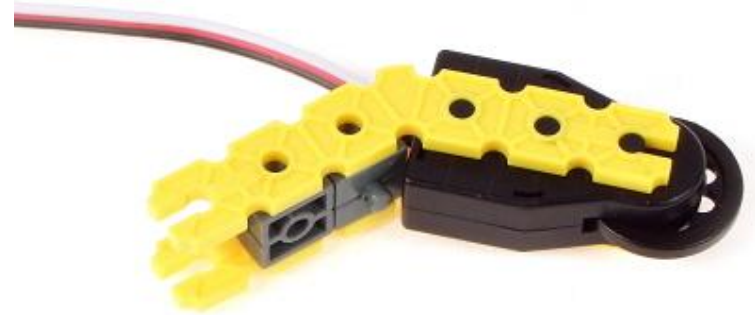
(S) X 2



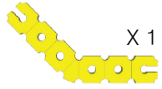
5



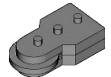
X 1



6



X 1



Touch sensor X 1



X 2



(S) X 2




7

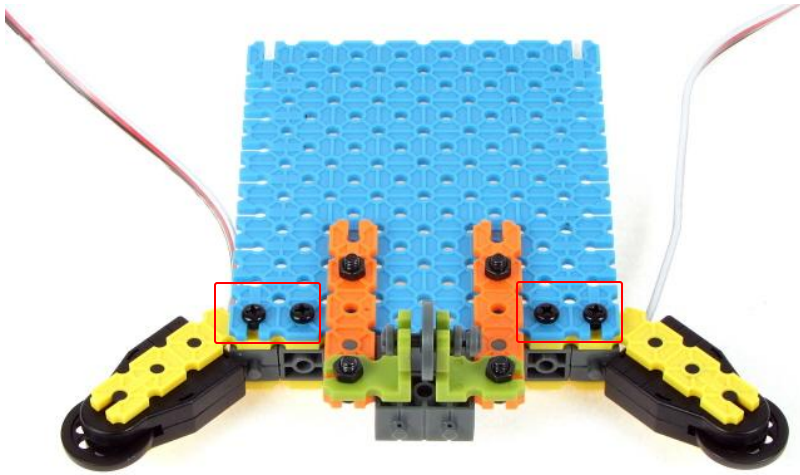


X 1




8

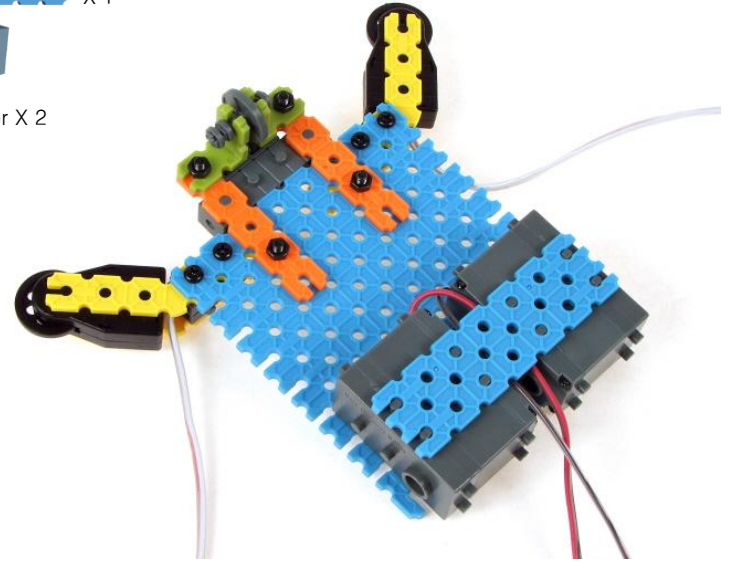
 (L) X 4



9

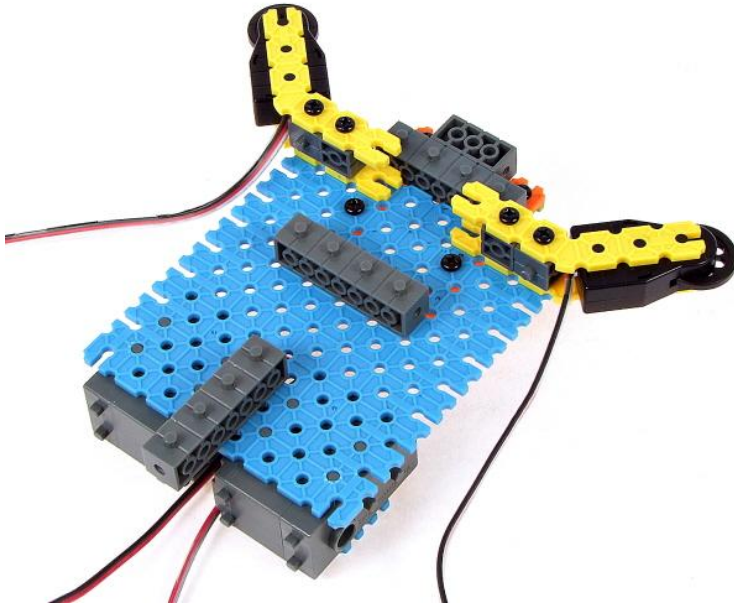
 X 1

 DC Motor X 2



10


 X 2

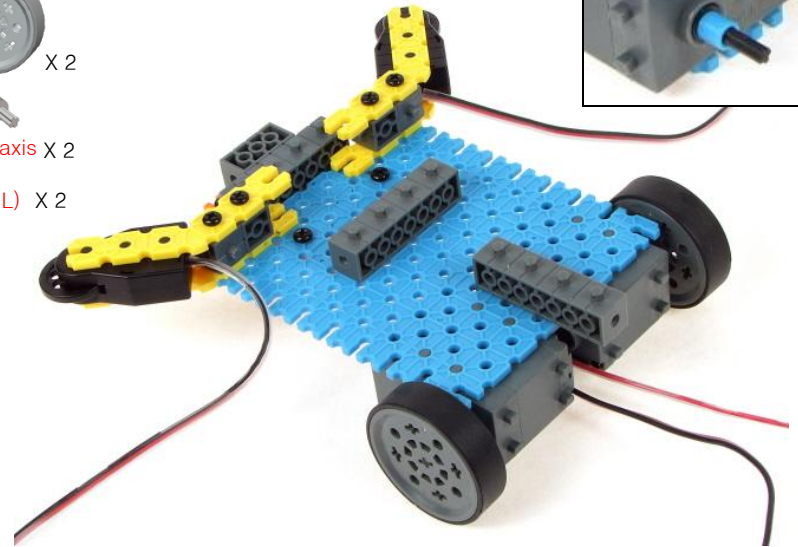


11

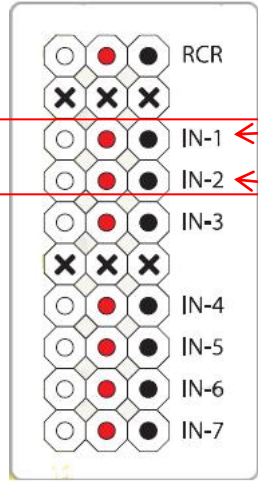
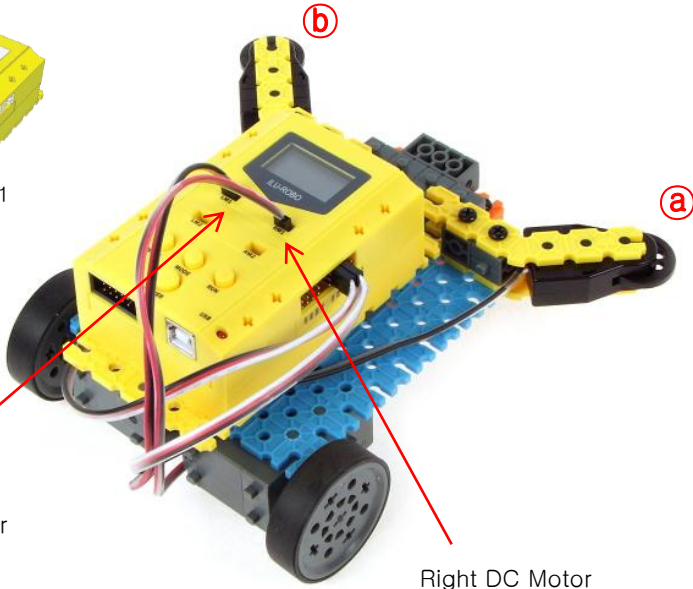
 X 2

 Motor axis X 2

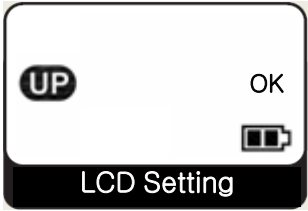
 (L) X 2



12

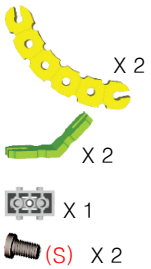


a Touch sensor
b Touch sensor

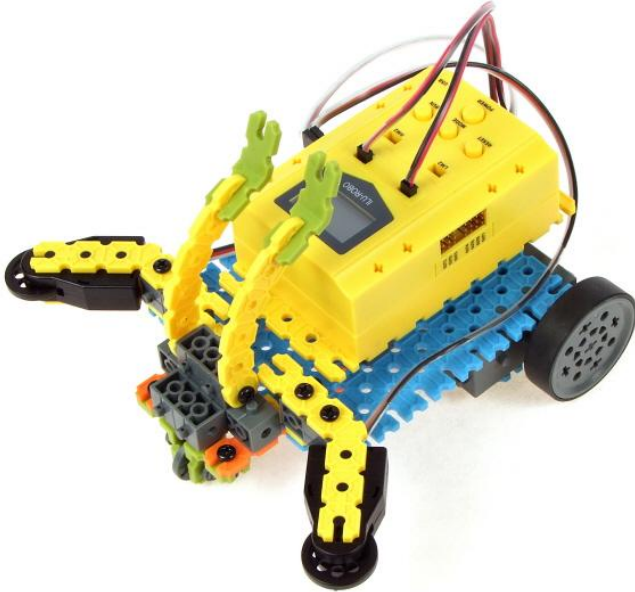


- This ladybird robot is for exercising the avoiding algorithm.
- Input module : 2 touch sensor
- Output module : 2 DC motor
- About the EQ-ROBO program algorithm, please refer to another manual.

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END



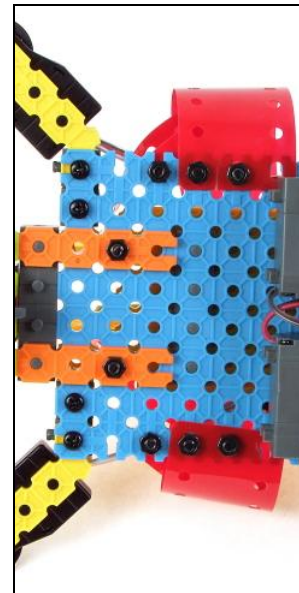
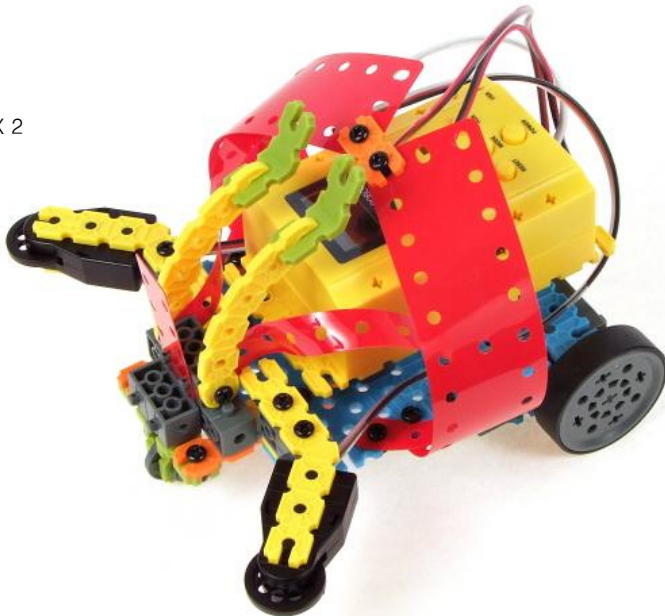
Decoration1

- X 2
- X 1
- X 2
- X 2

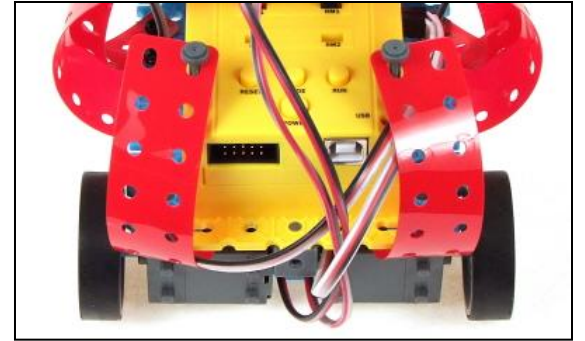
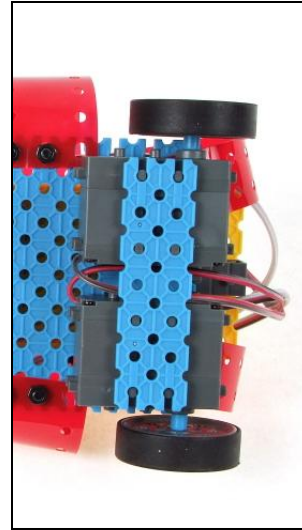
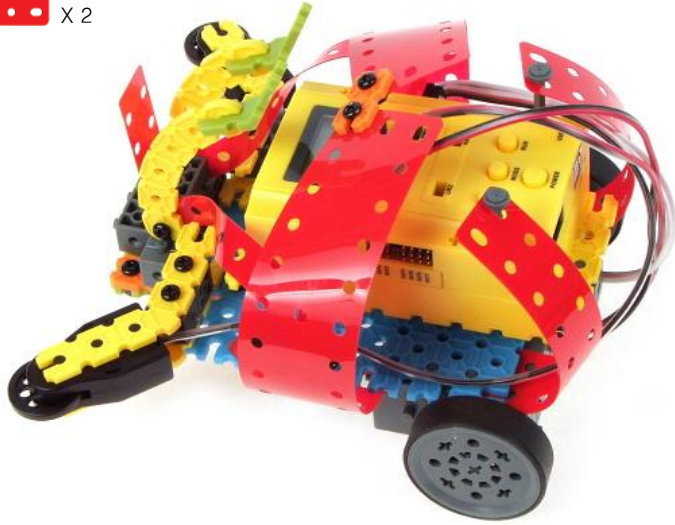


Decoration2

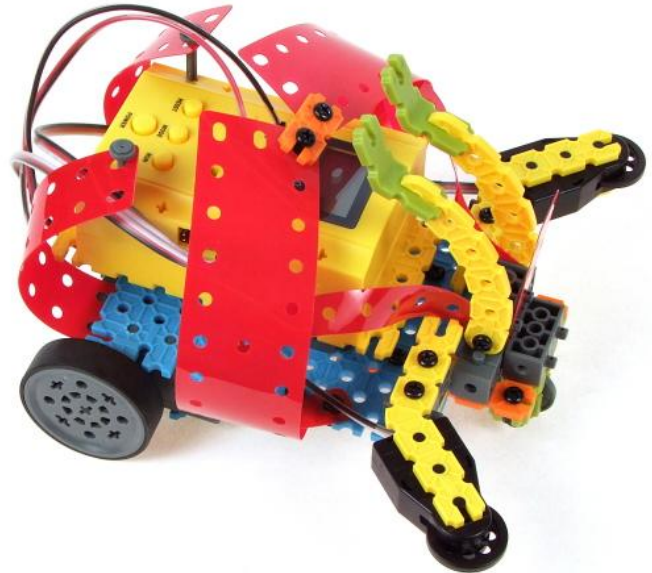
- X 2
- X 1
- X 6
- X 6



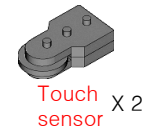
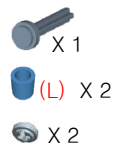
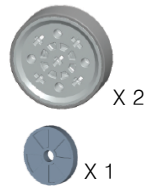
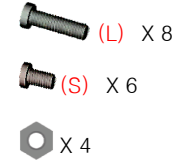
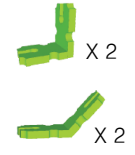
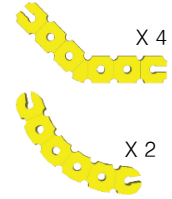
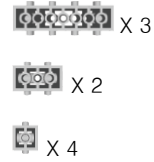
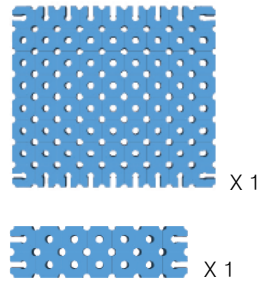
Decoration3



END



Part List of a Ladybird robot



Decoration part list

