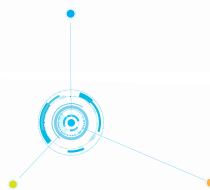
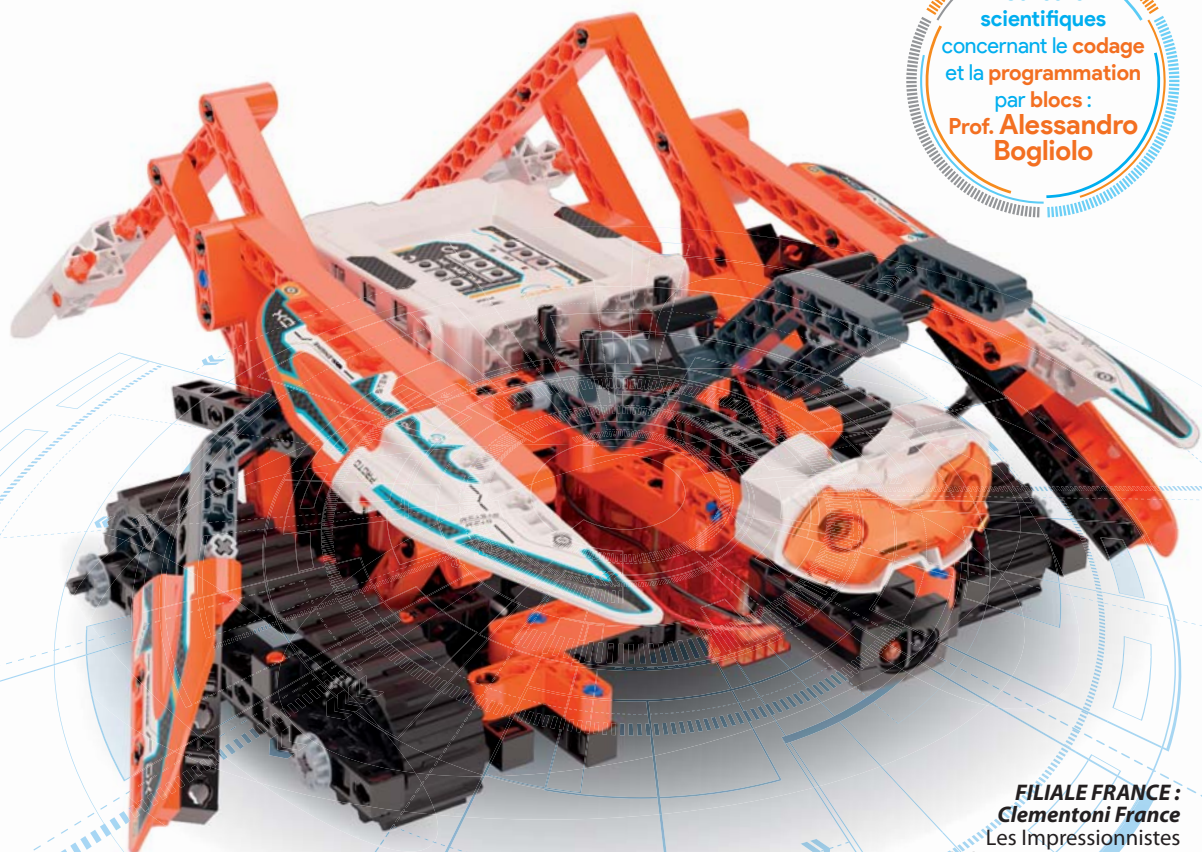


RoboMaker[®]

le laboratoire de robotique éducative **pro**



X2 • SPIDER



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Notice à lire et à conserver pour toute consultation ultérieure.



Assemblage

1

26

26

1

1

1:1

1

X2

X2

X2

1

x2

x2

26

X2

x2

2

x2

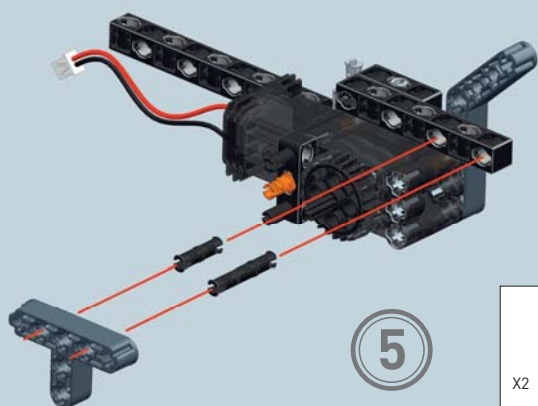
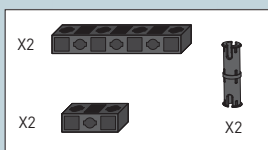
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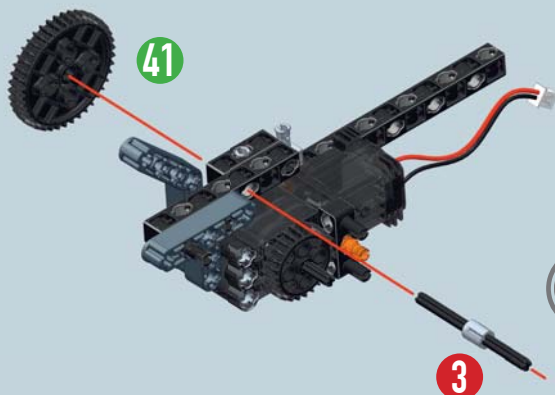
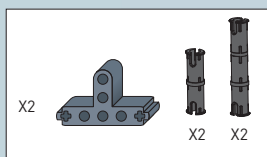
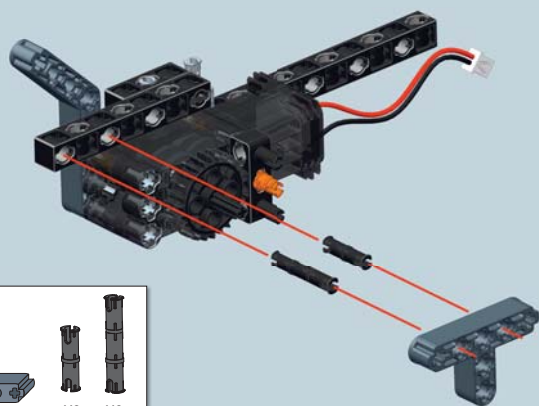
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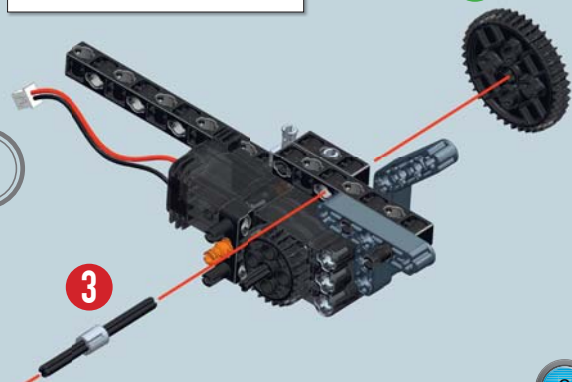
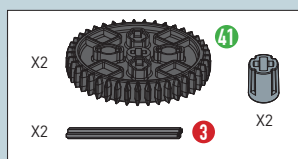
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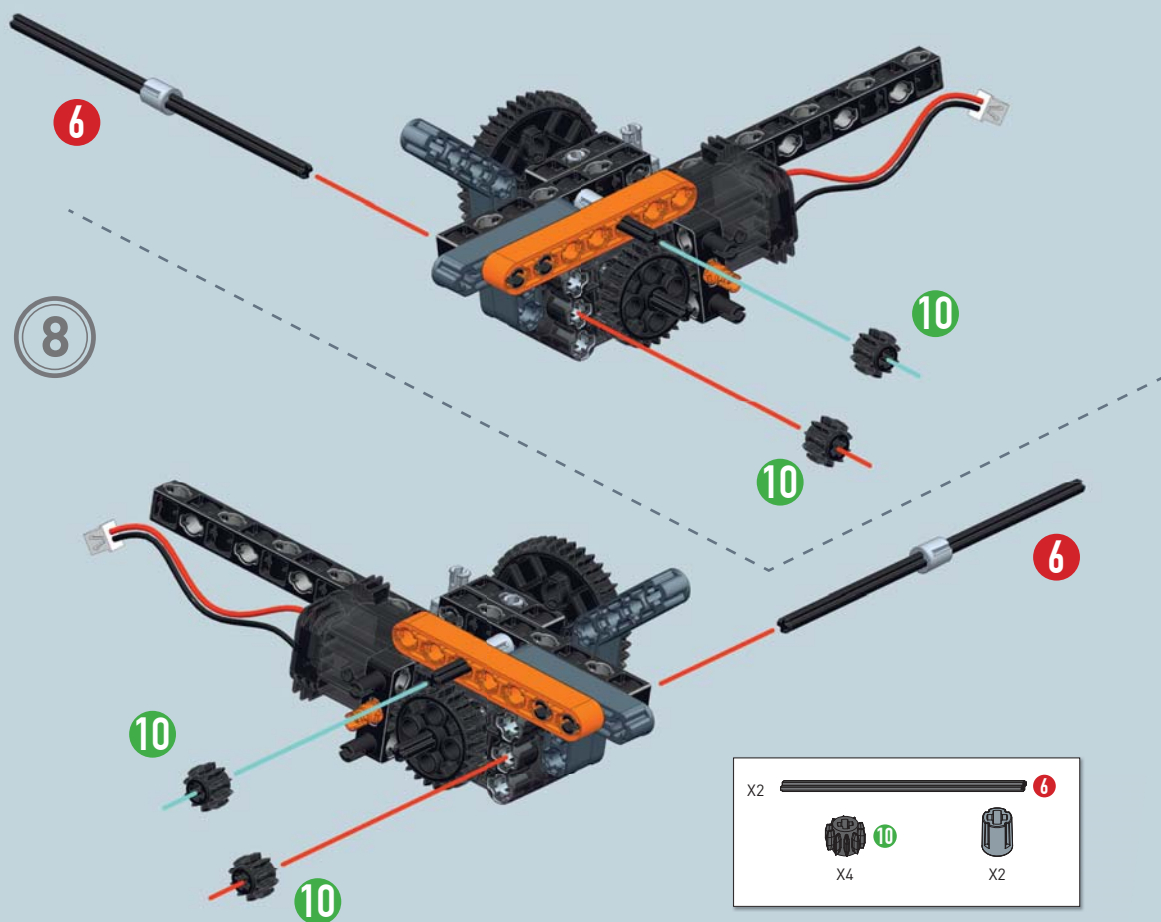
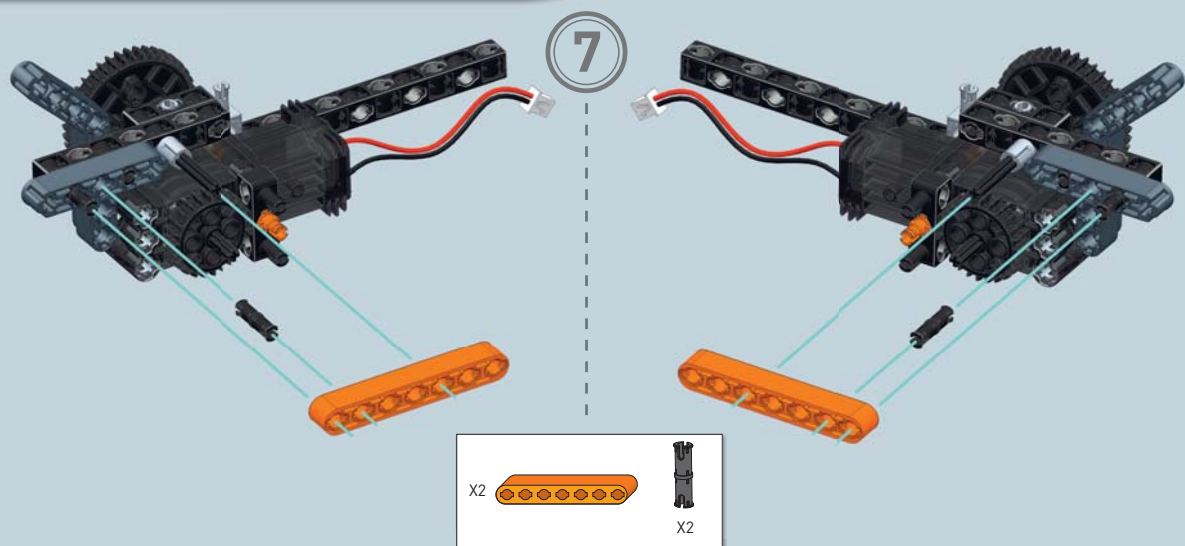


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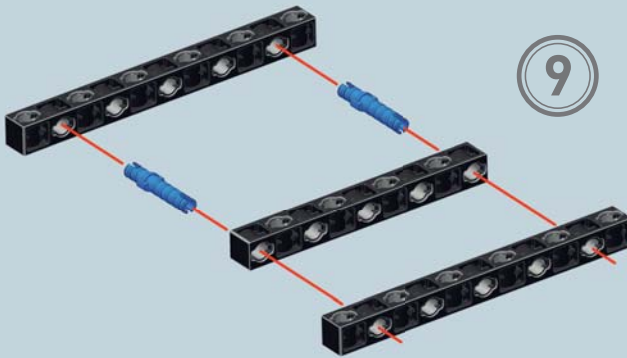
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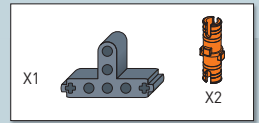
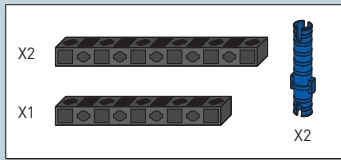


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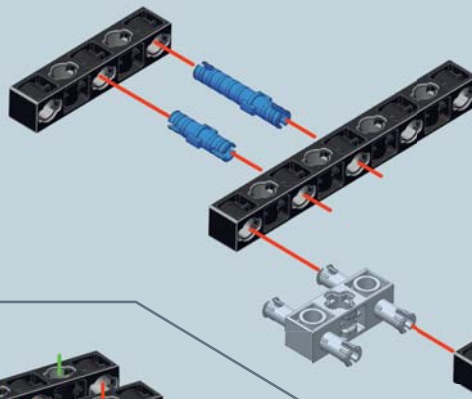
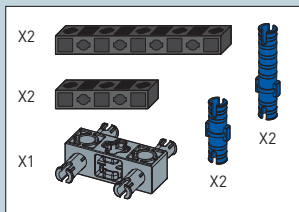
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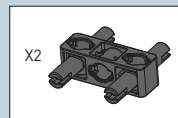
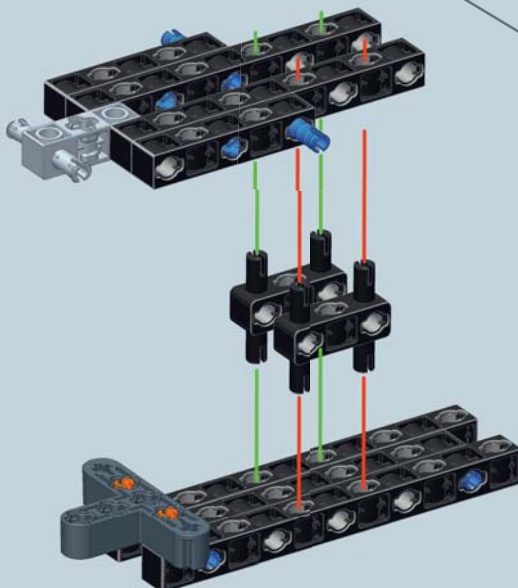
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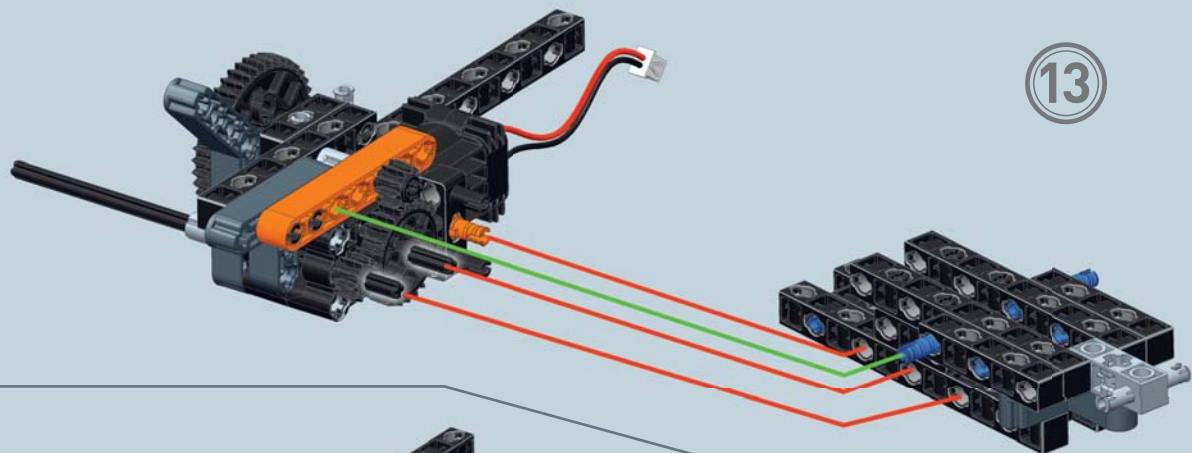
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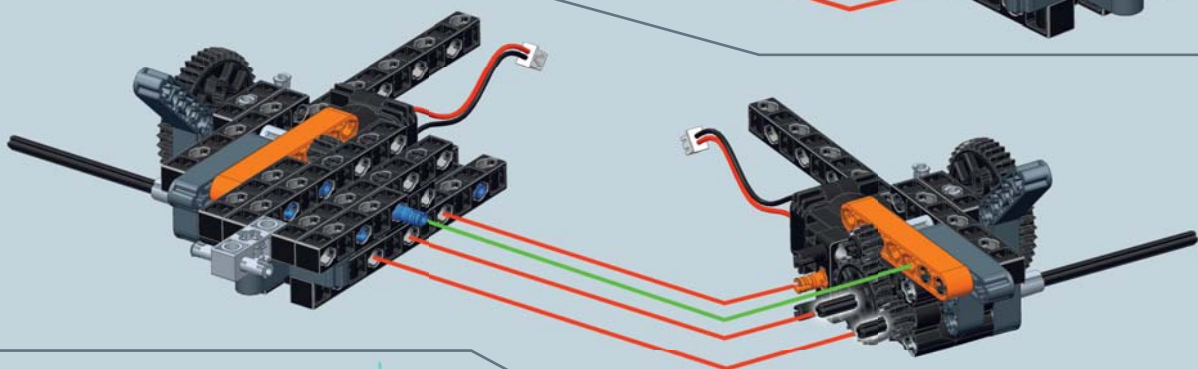
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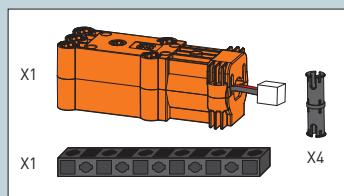
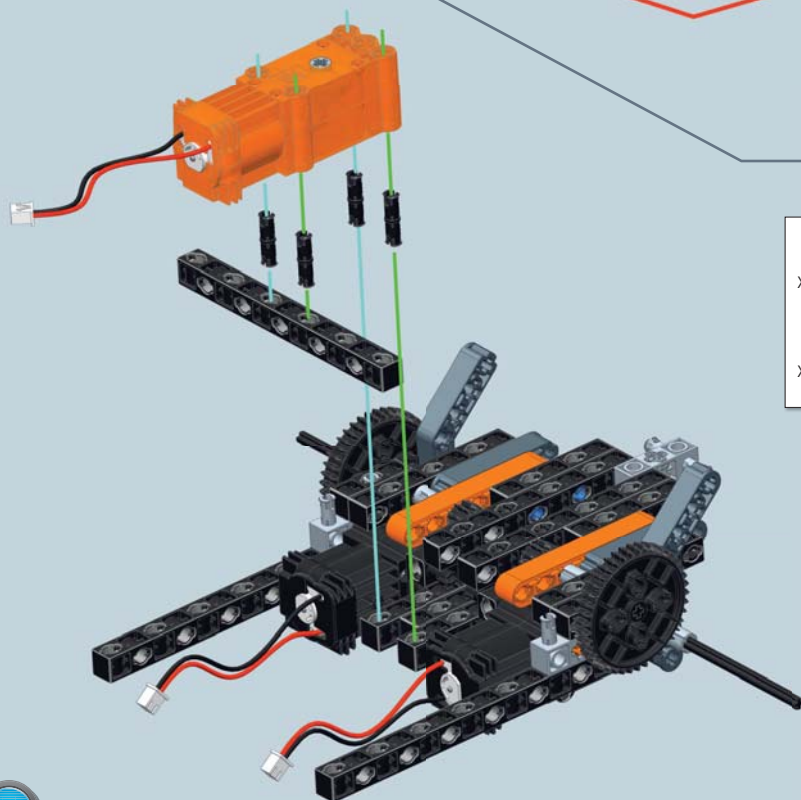
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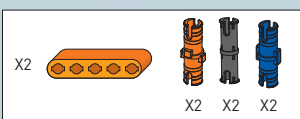
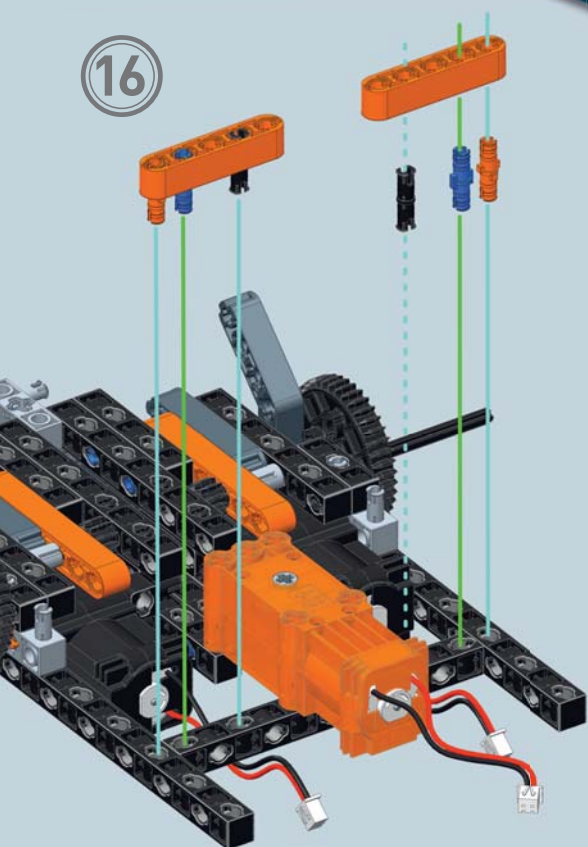


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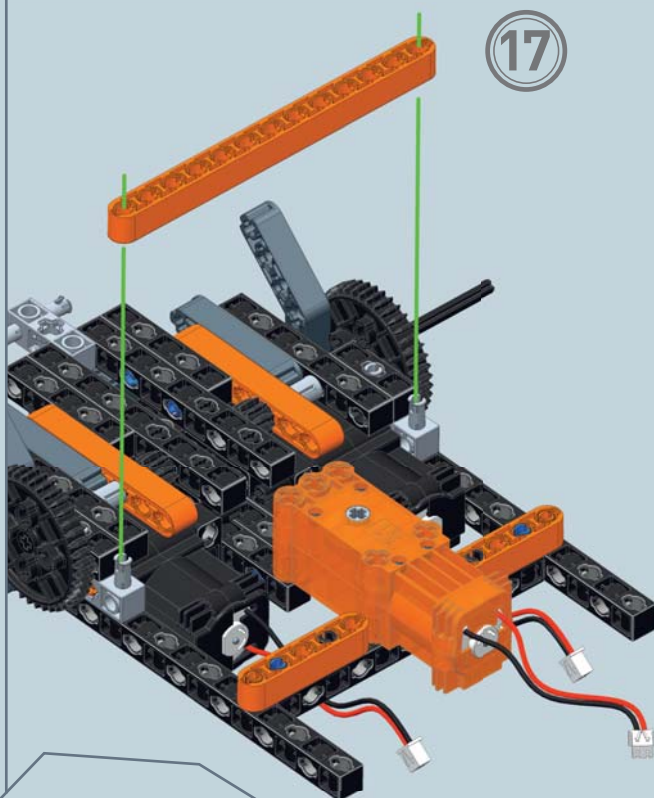


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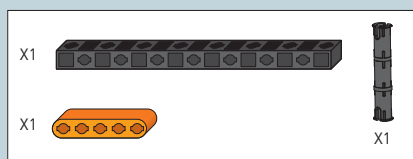
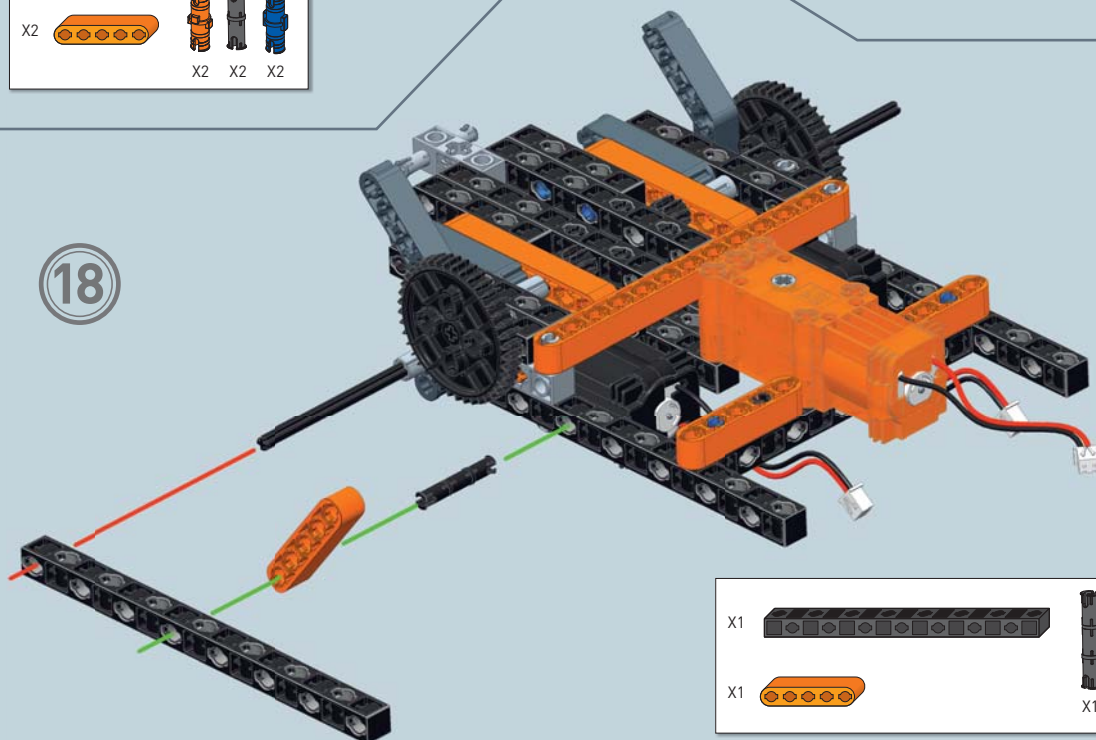
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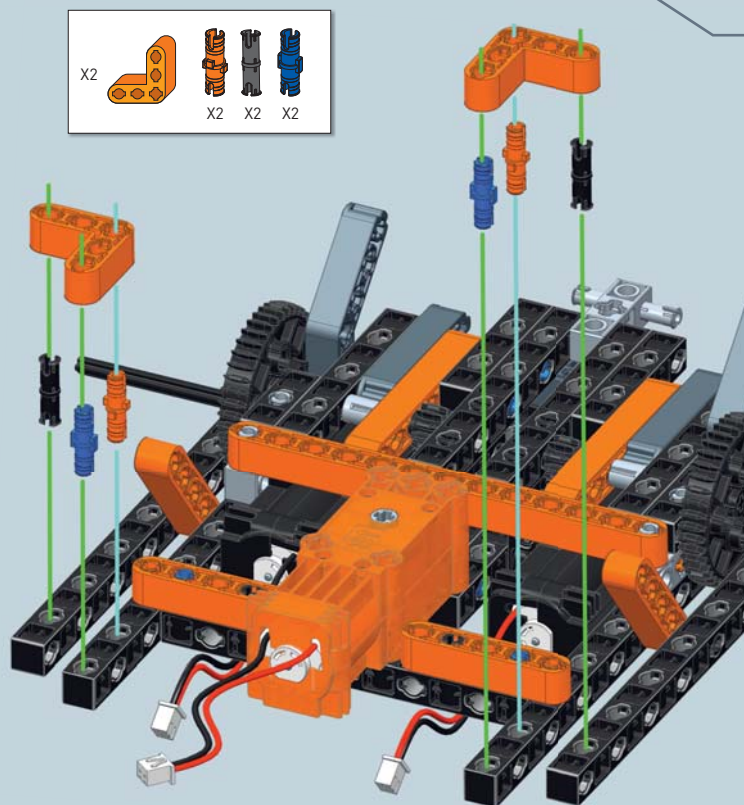
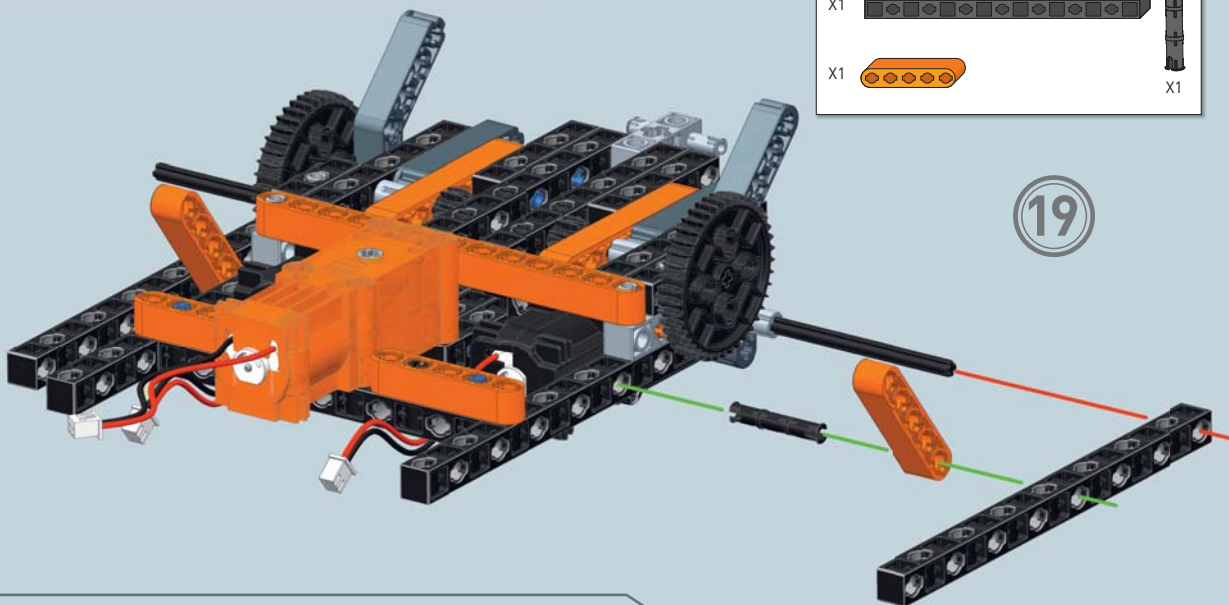


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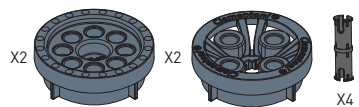
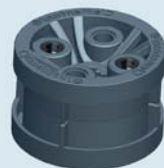


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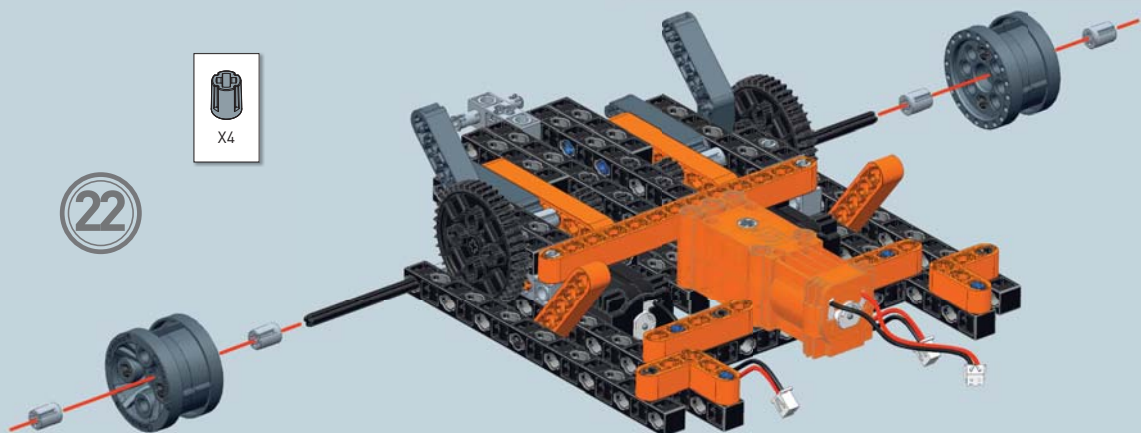




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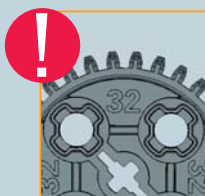
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32

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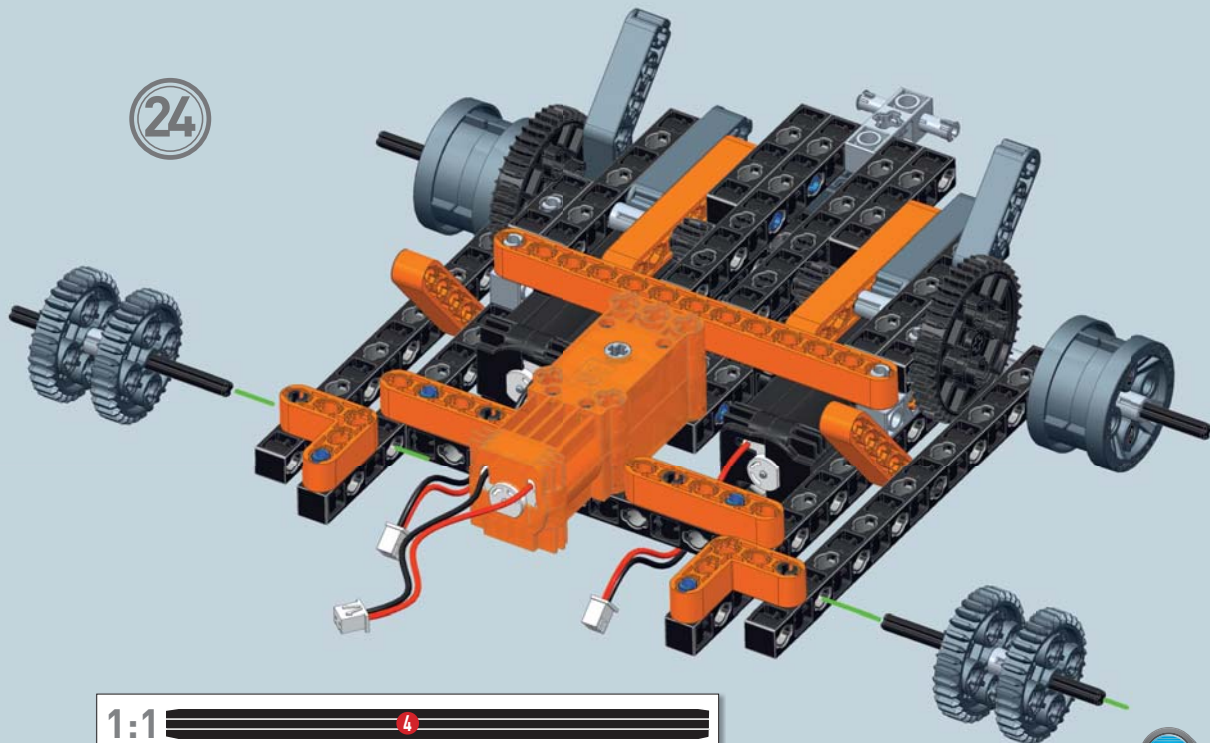


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X2

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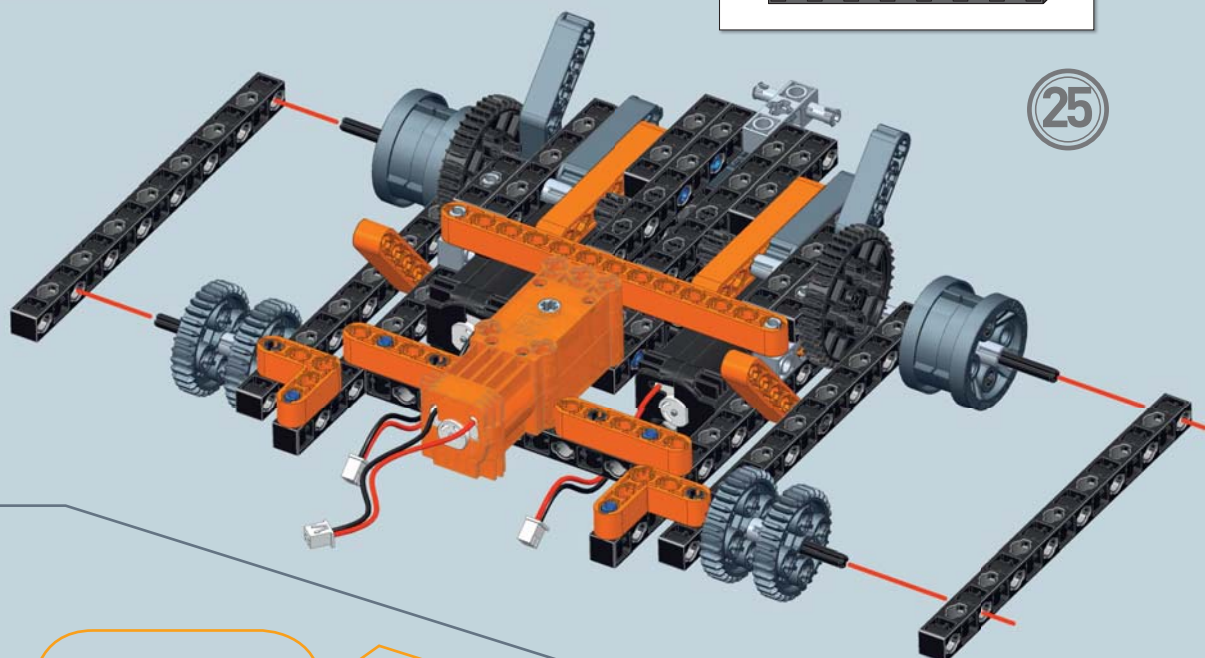
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X2



25



X2

X2



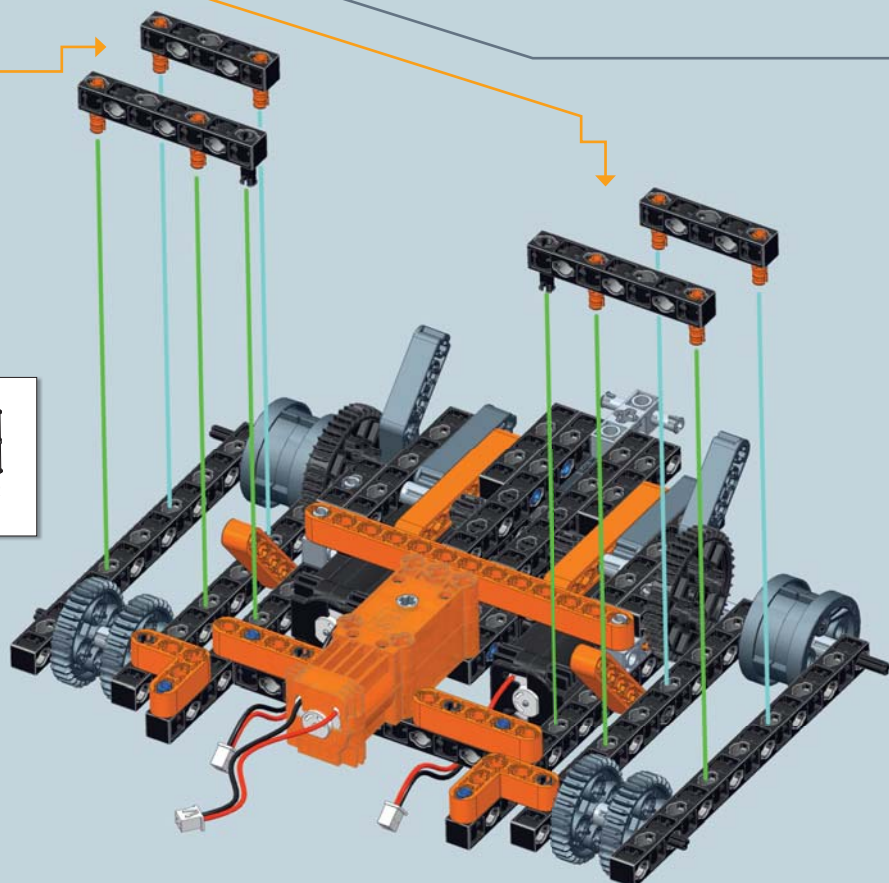
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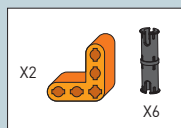
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X2

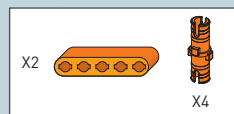
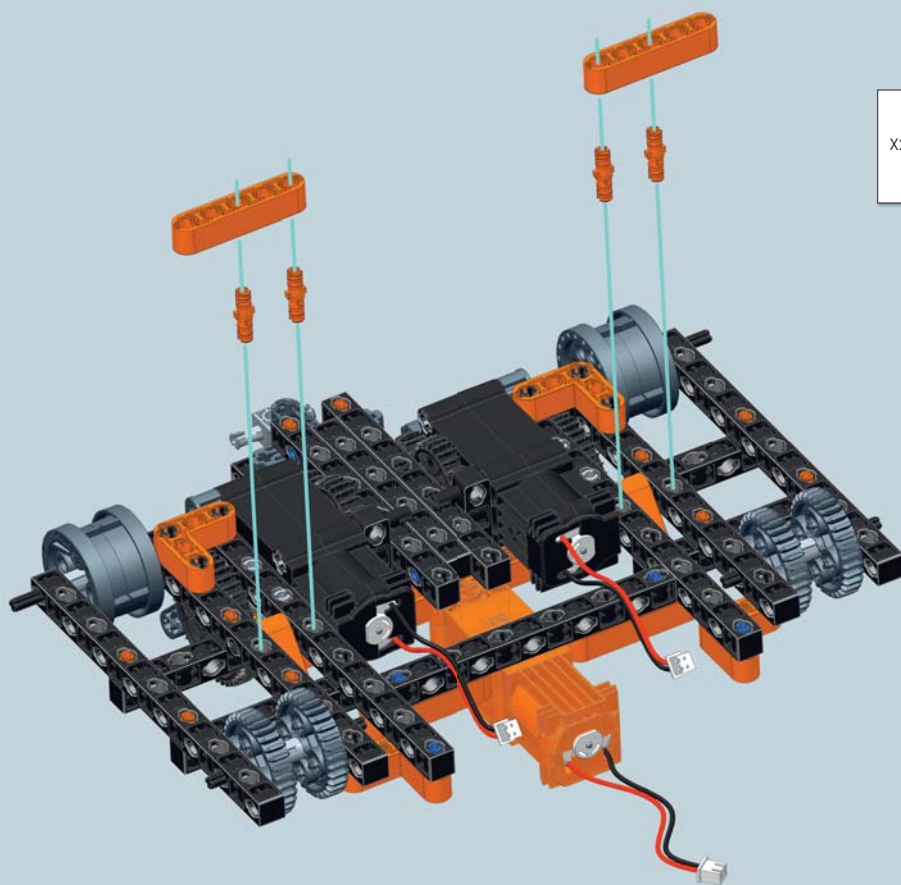
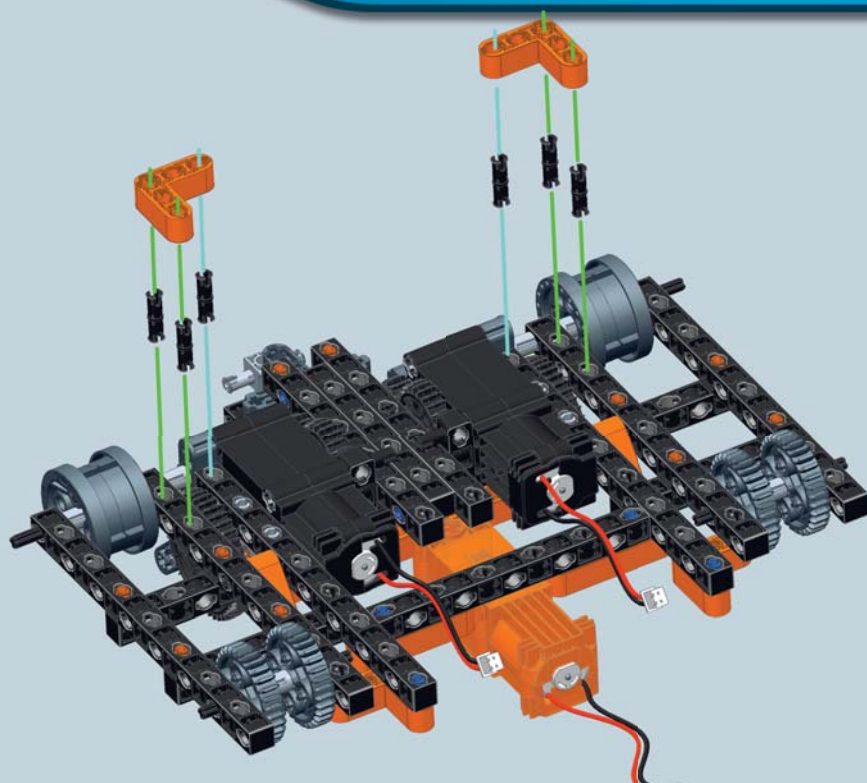


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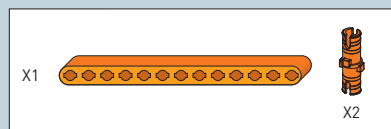
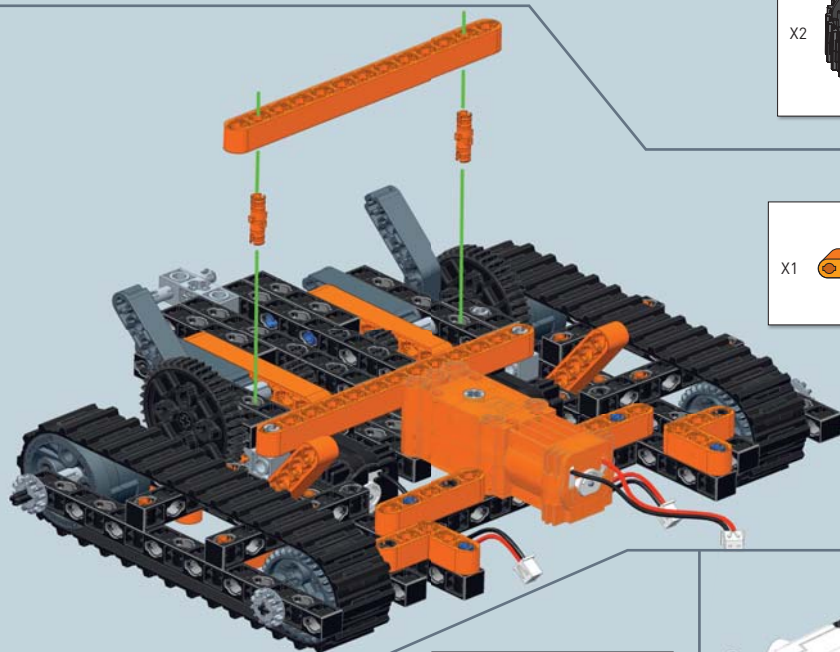
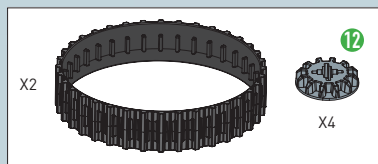
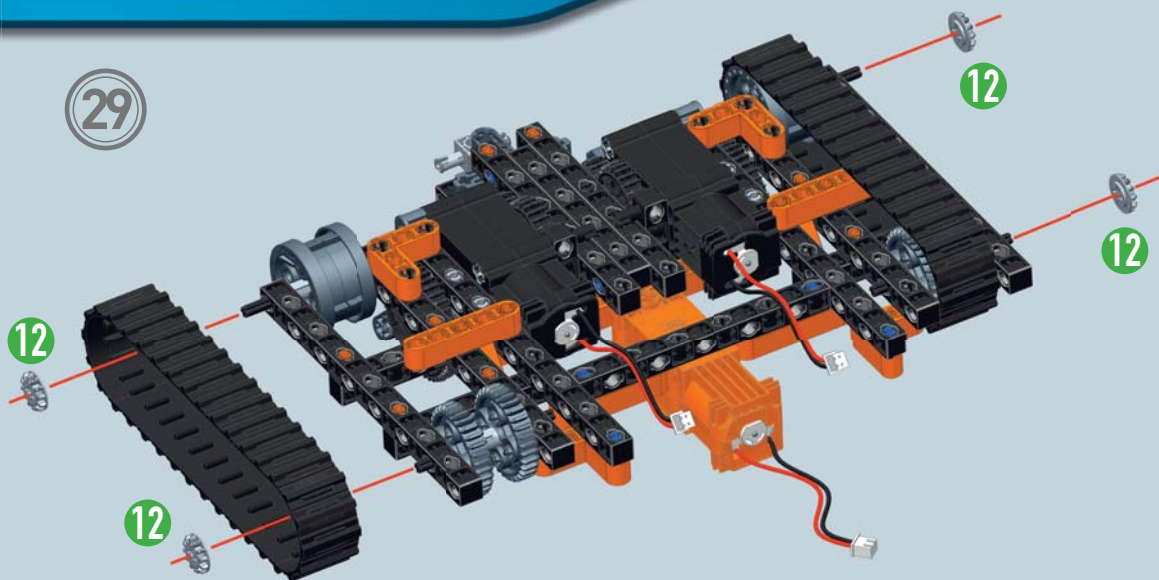


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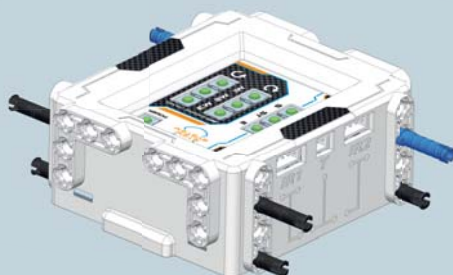
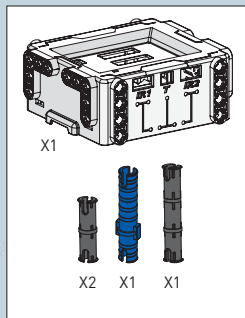
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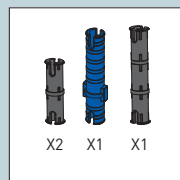
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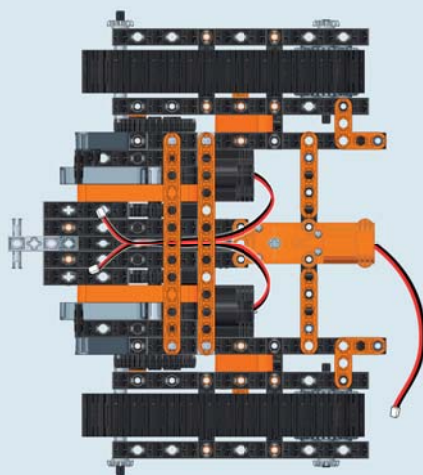


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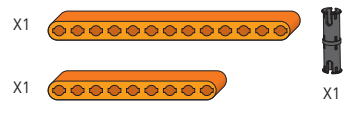
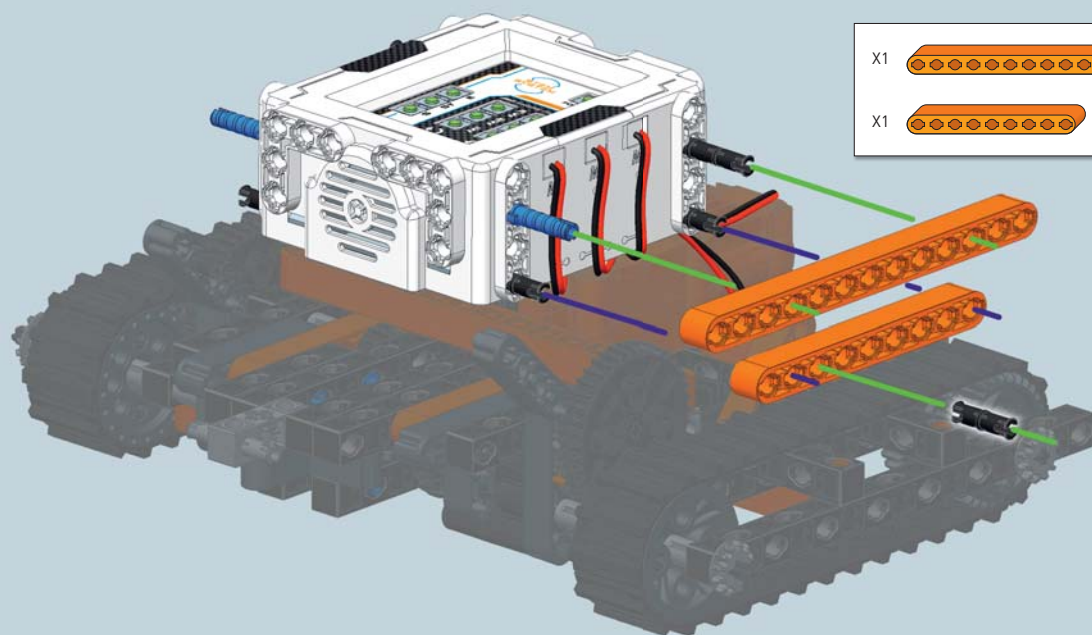
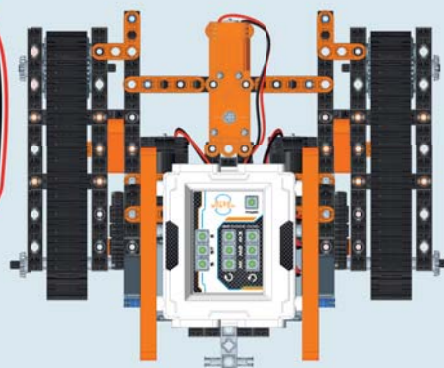
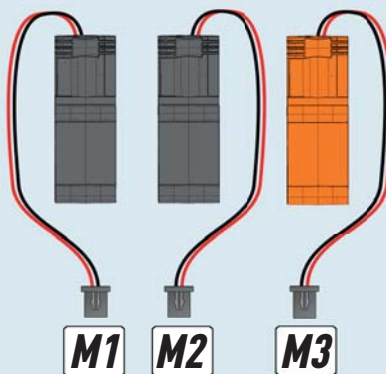


POSITIONNE LES CÂBLES

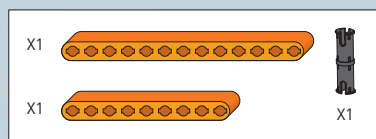
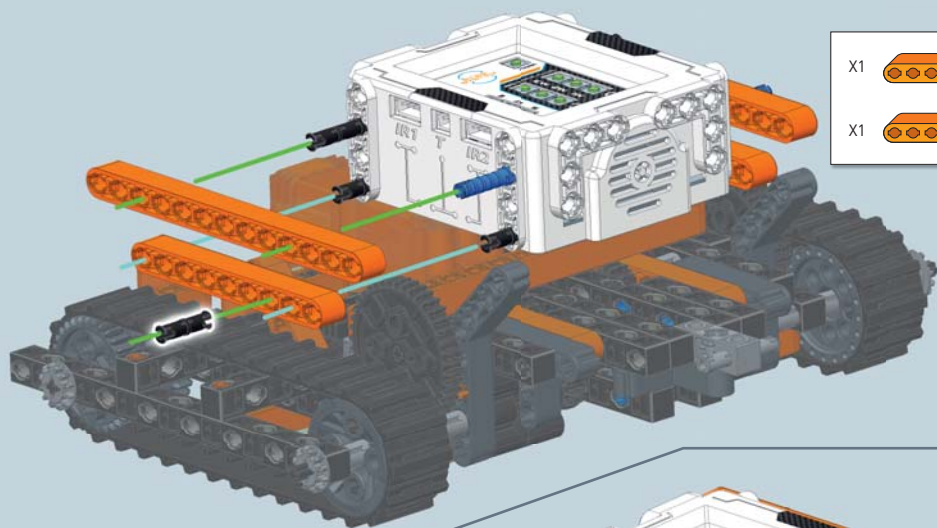
Avant d'effectuer les raccordements au module, fais passer les câbles des deux moteurs noirs sous les deux barres orange à 13 trous, comme représenté sur la figure.

CONNECTE LES MOTEURS AU MODULE CENTRAL

Orienté le modèle comme sur l'image, puis connecte le moteur de gauche au port M1 et le moteur de droite au port M2. Enfin, connecte le moteur orange au port M3.

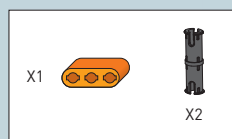
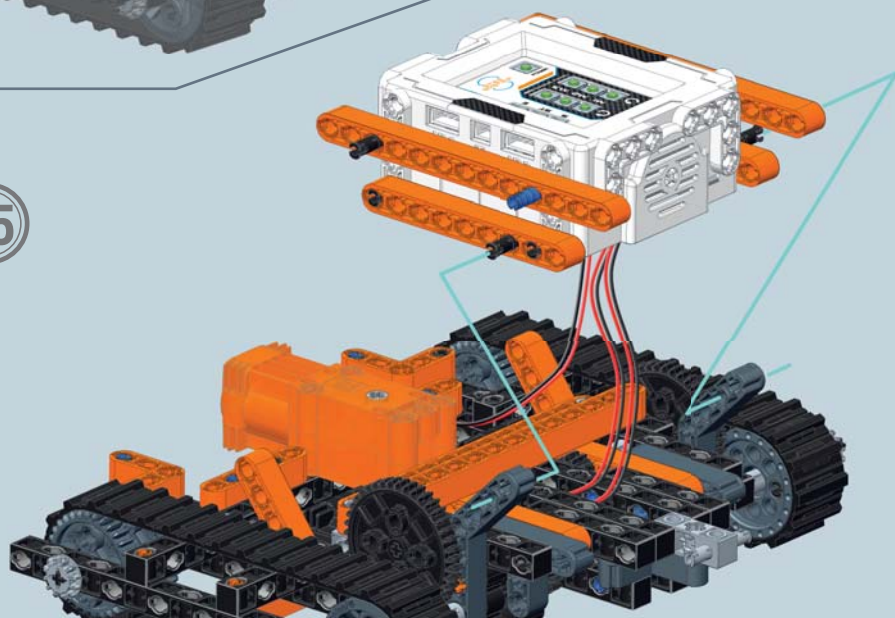


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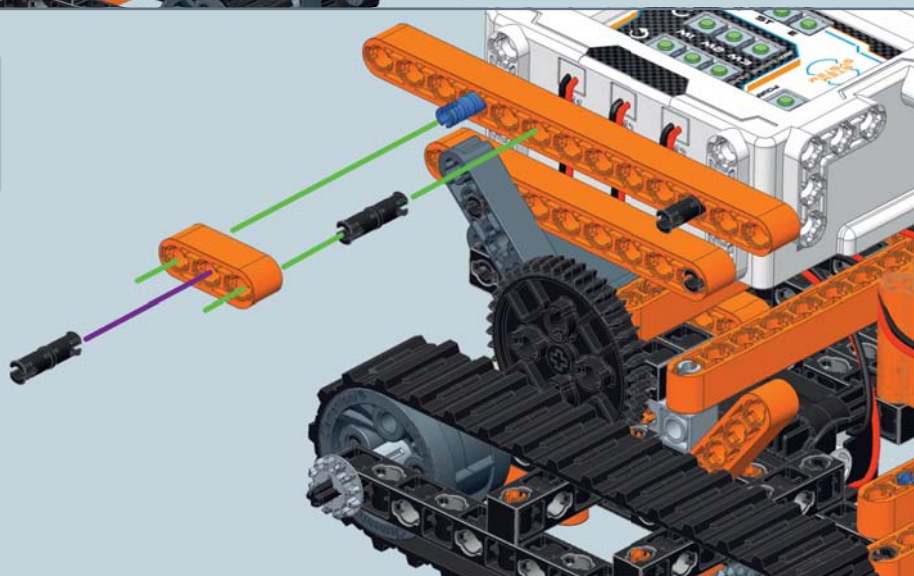


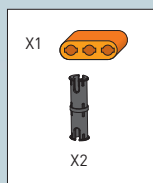
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35

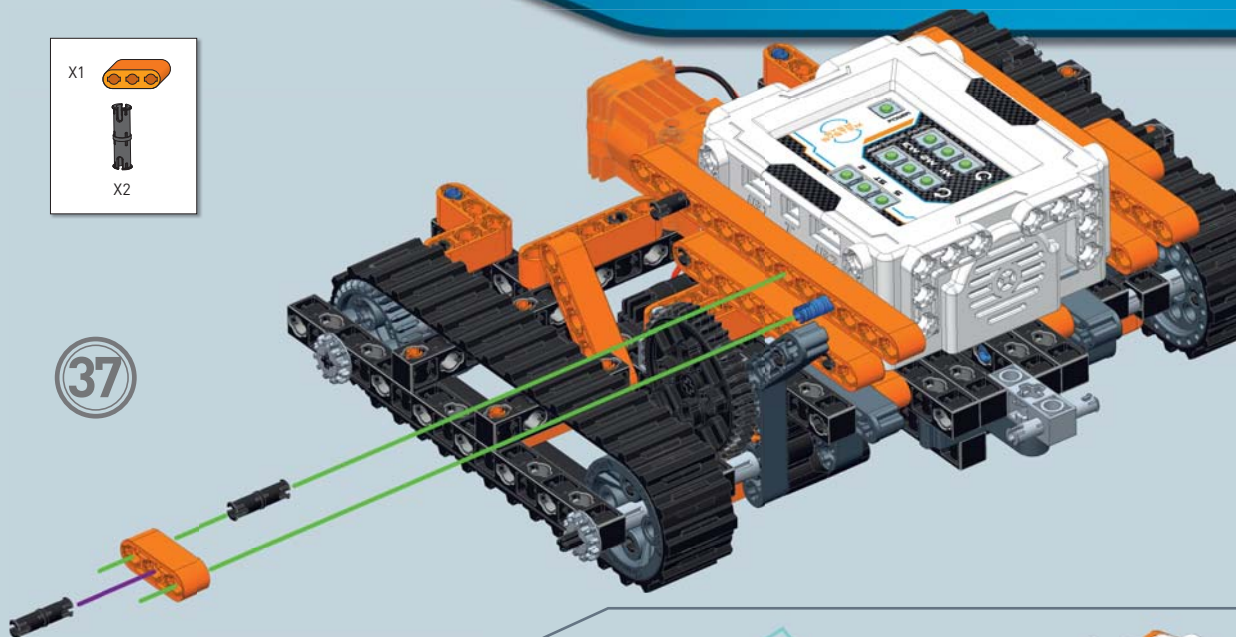


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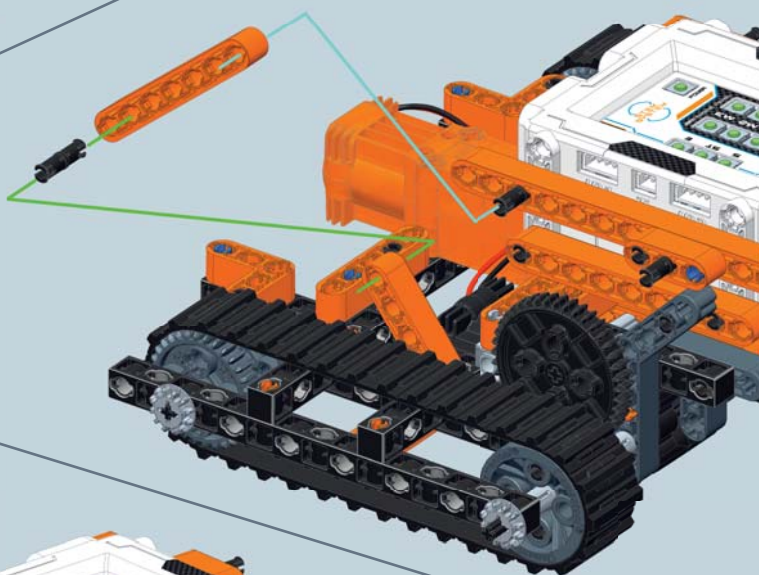
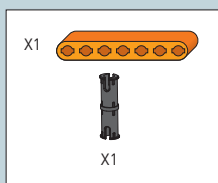




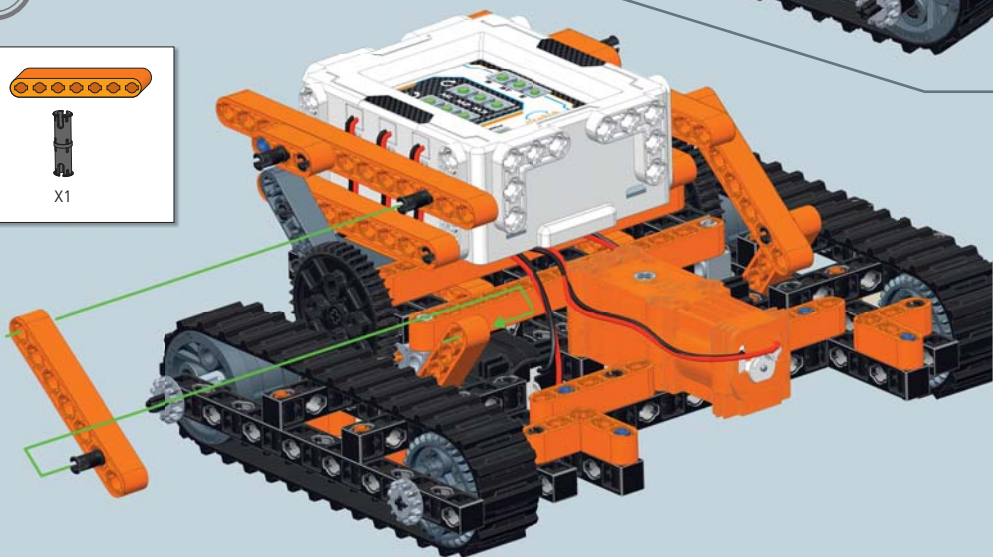
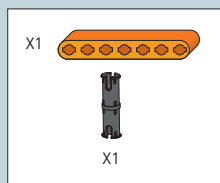
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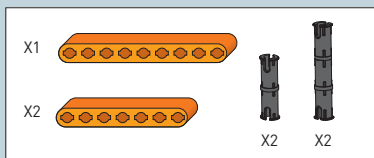
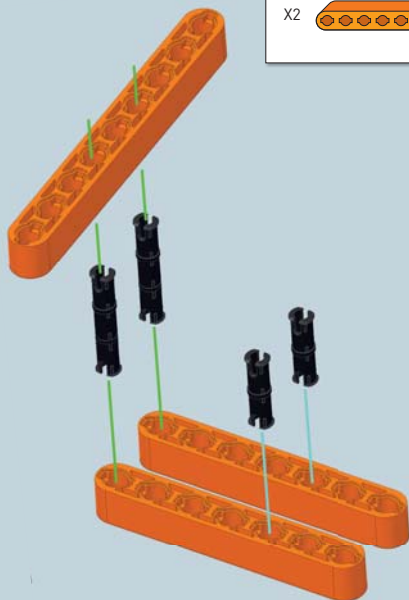


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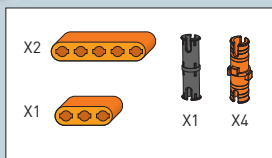


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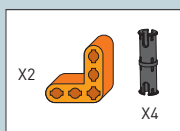
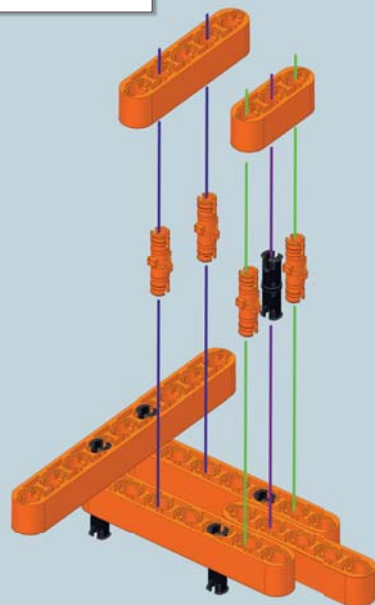




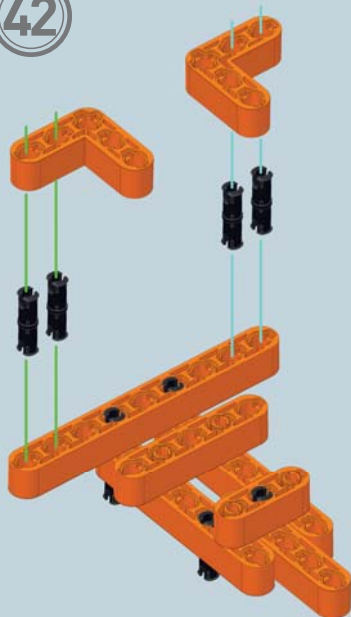
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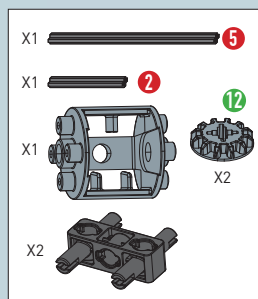
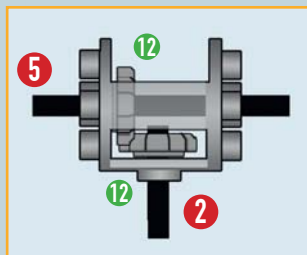
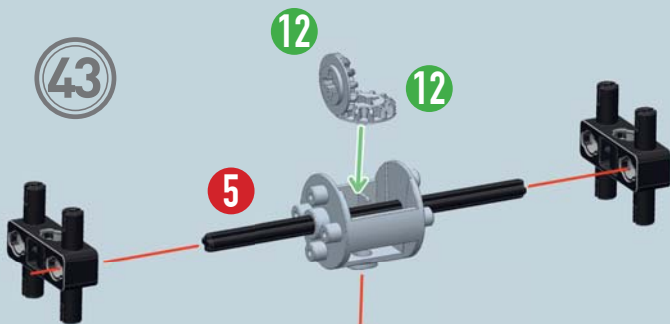
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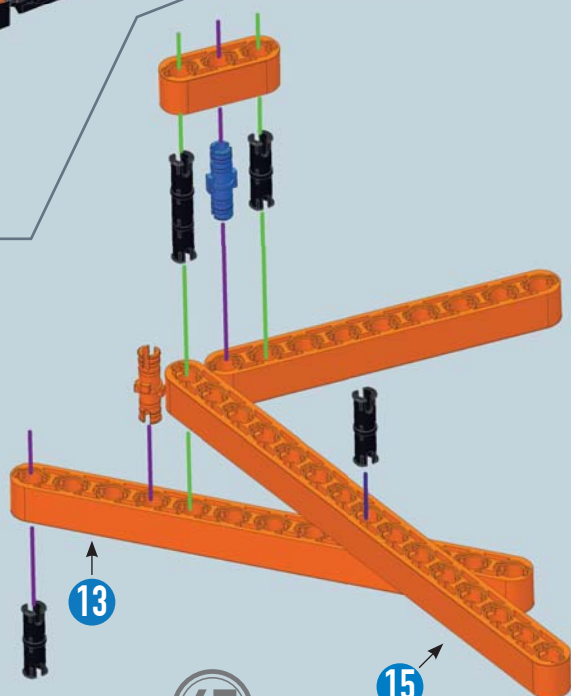
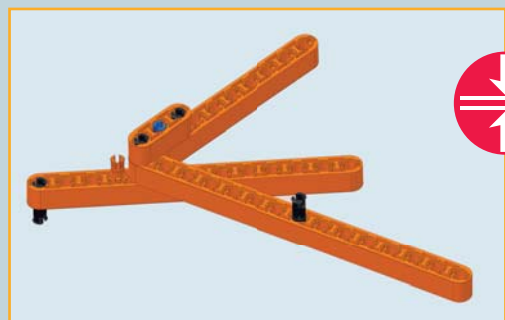
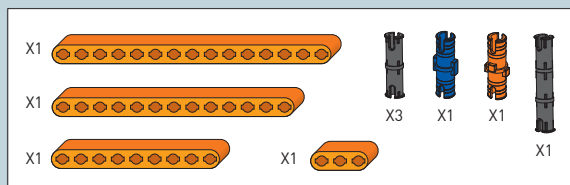
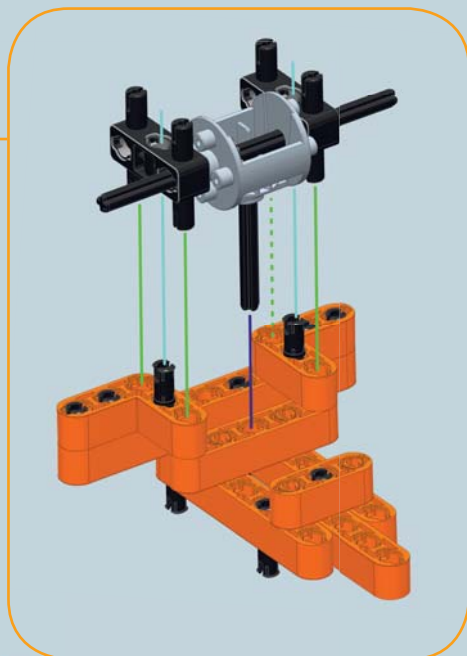
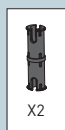
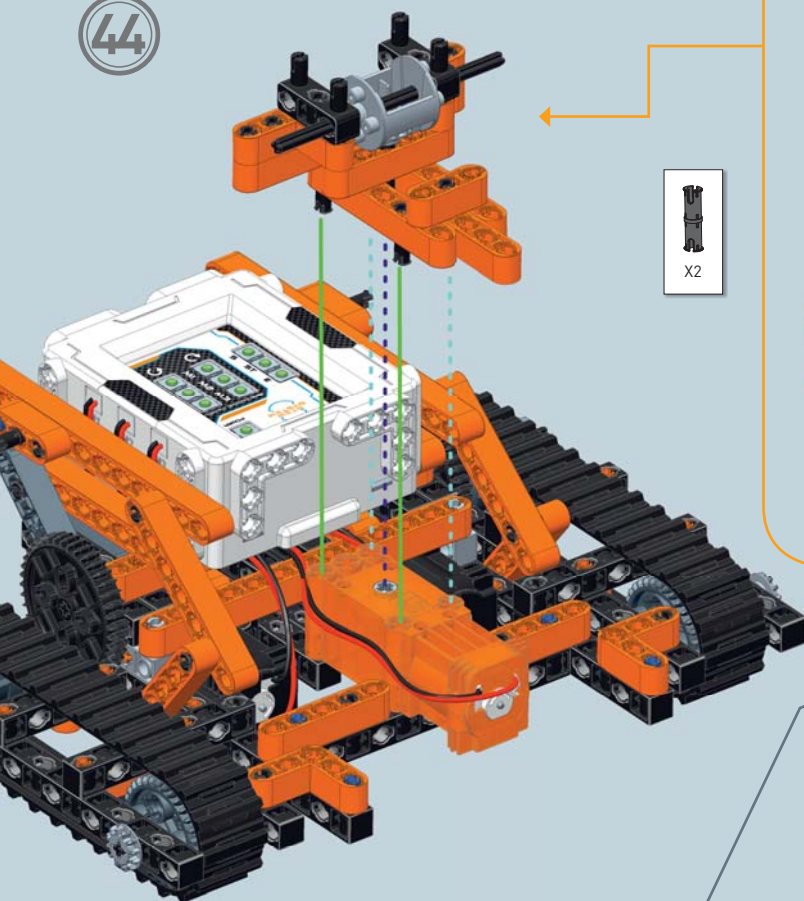
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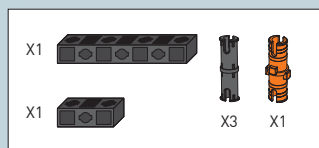
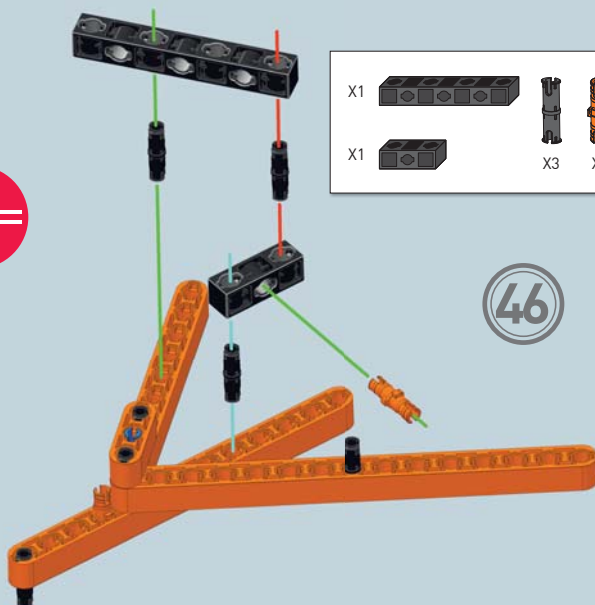
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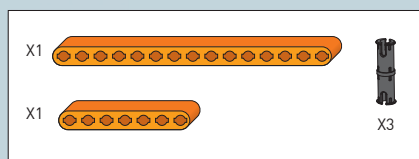
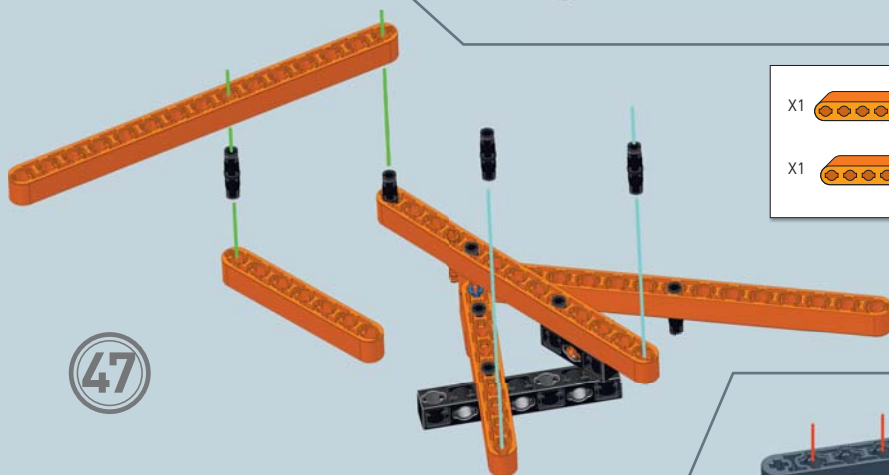
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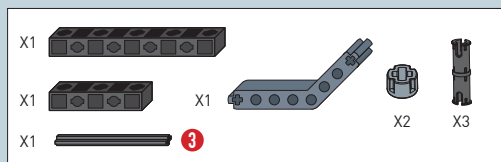
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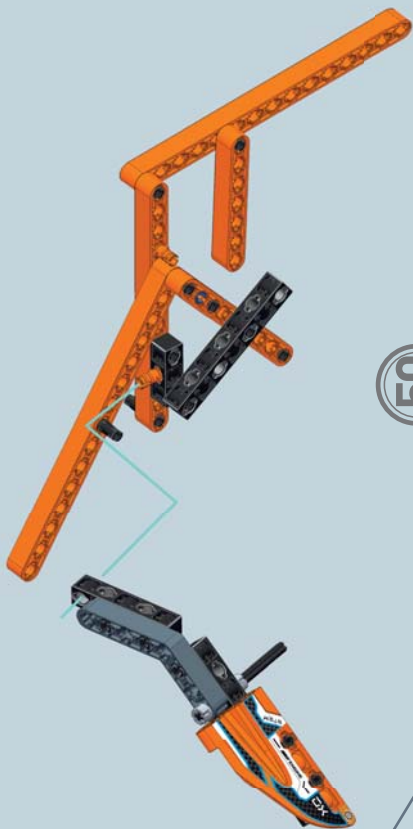


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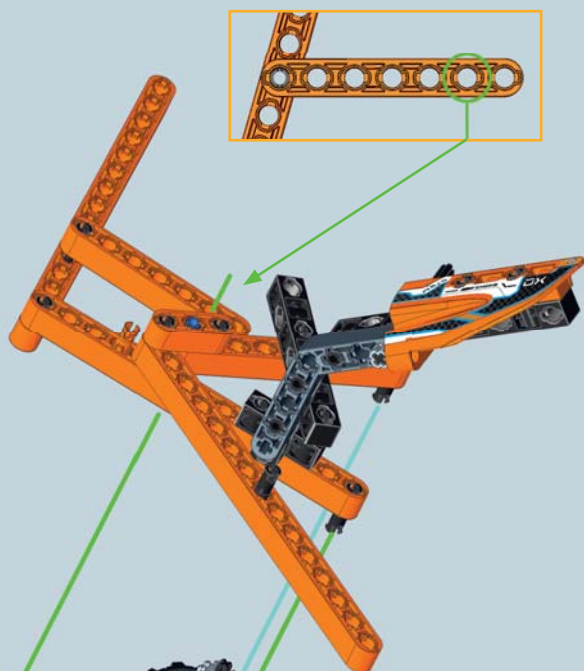


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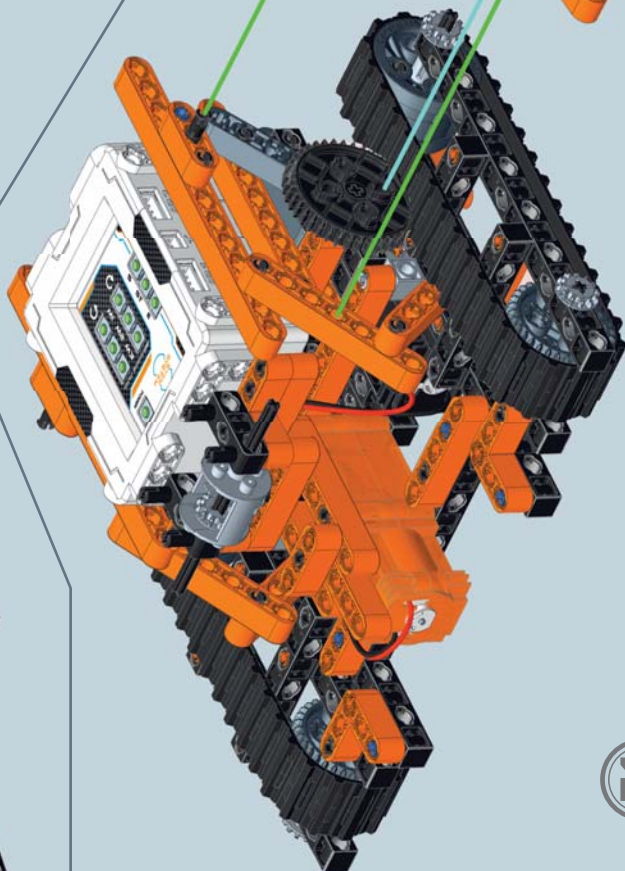




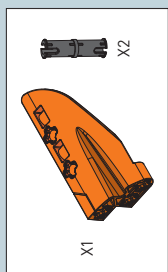
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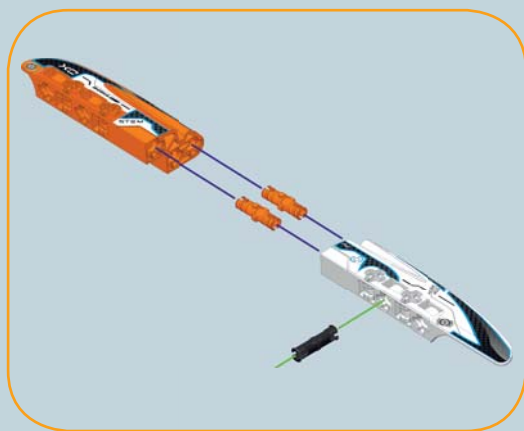
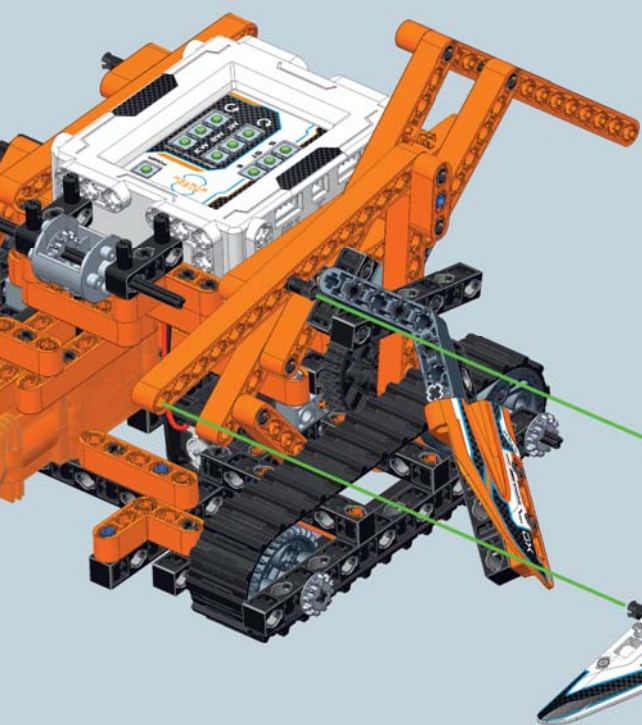
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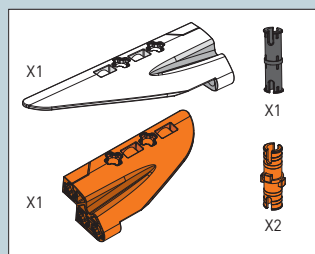
X2

X1

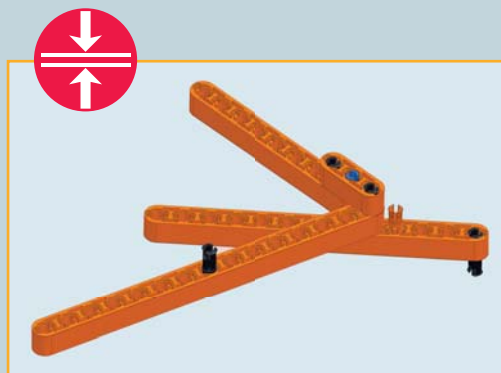
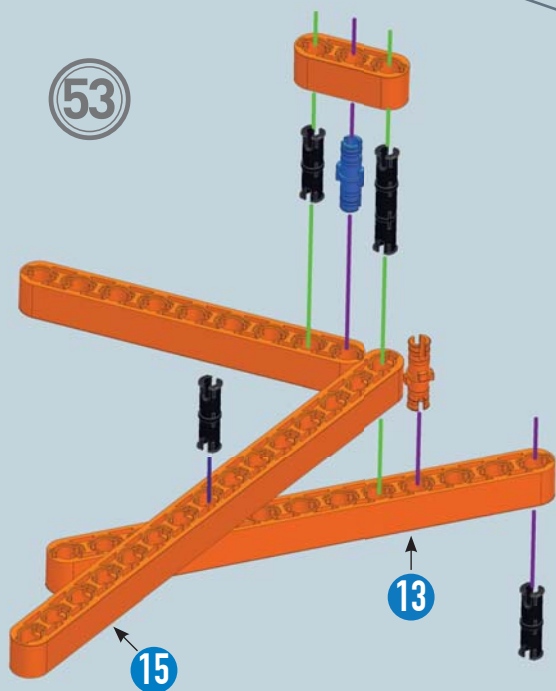
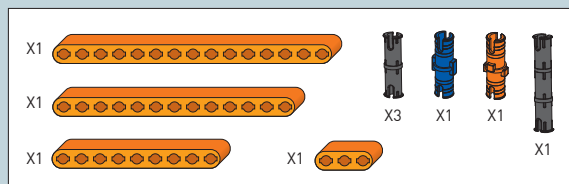


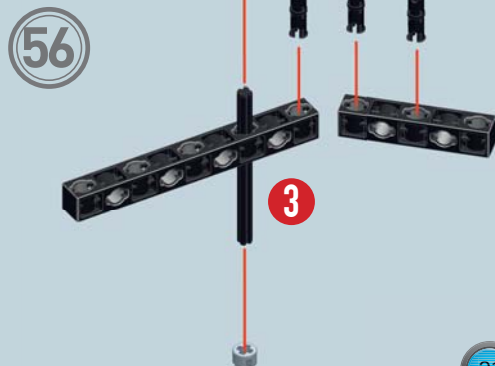
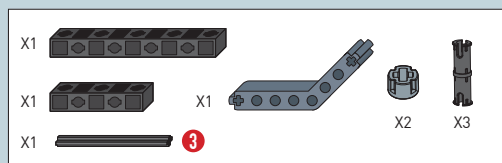
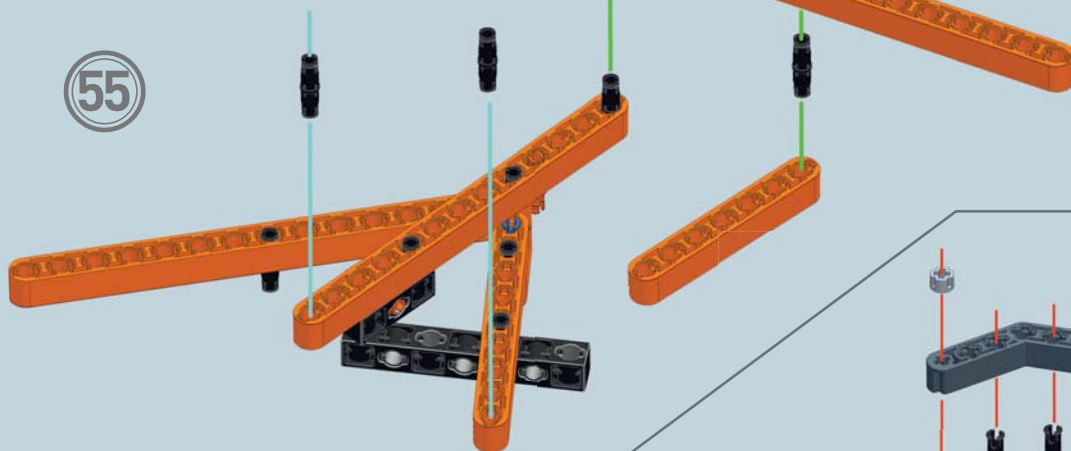
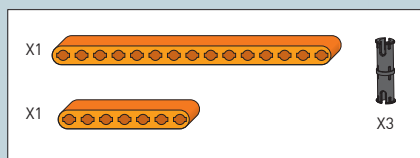
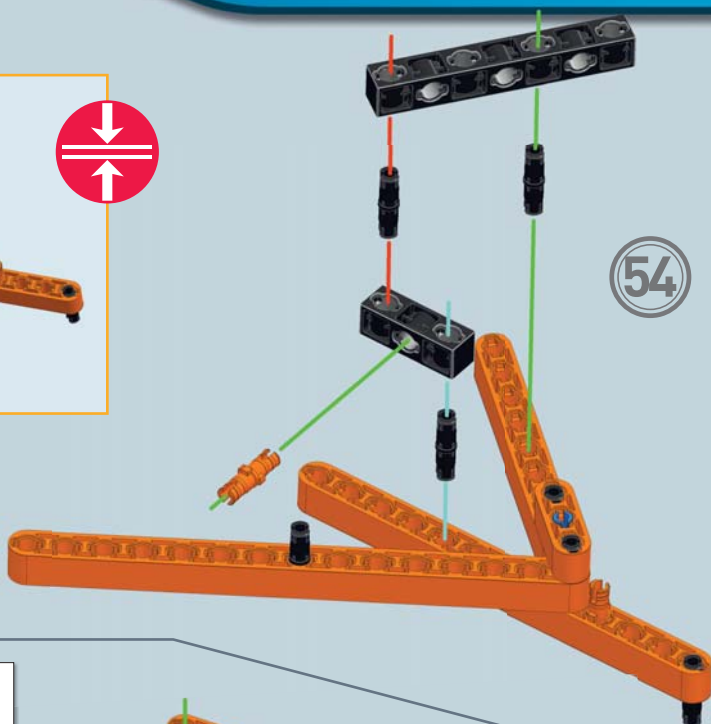
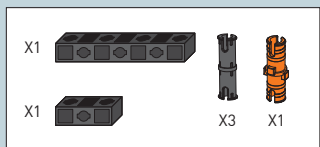


52

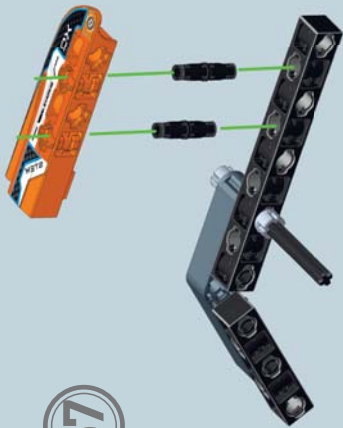


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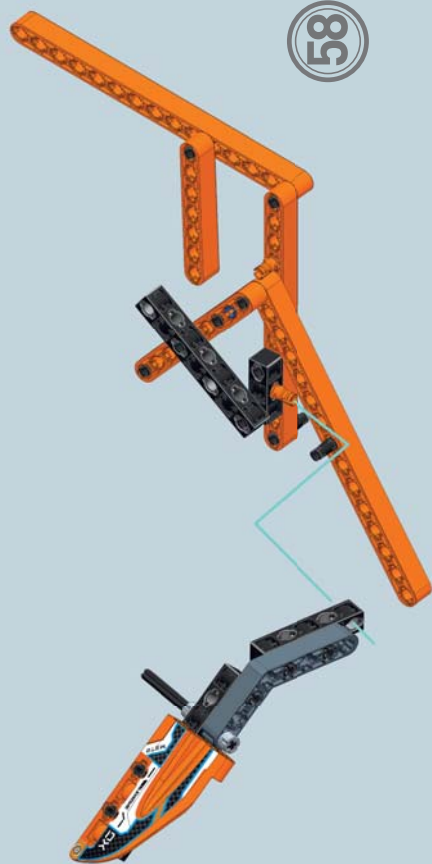




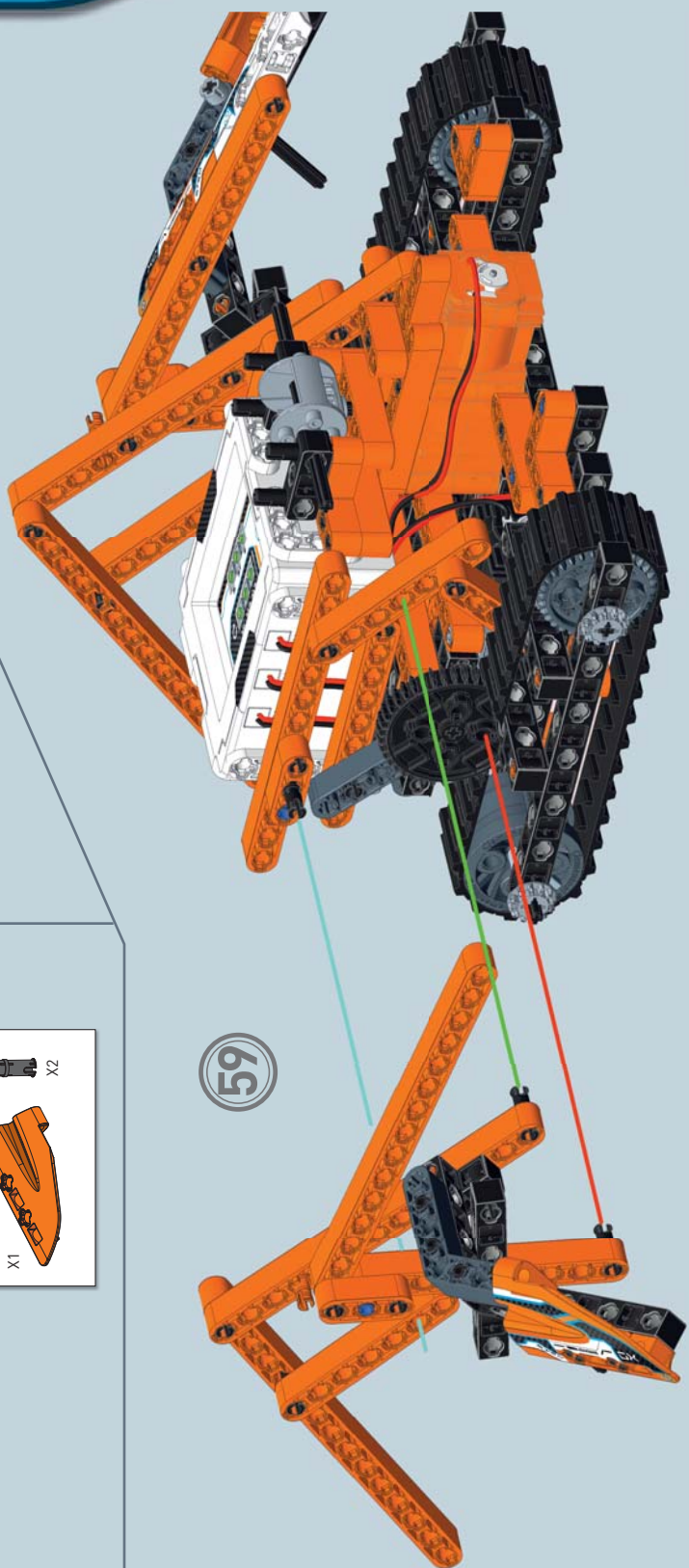
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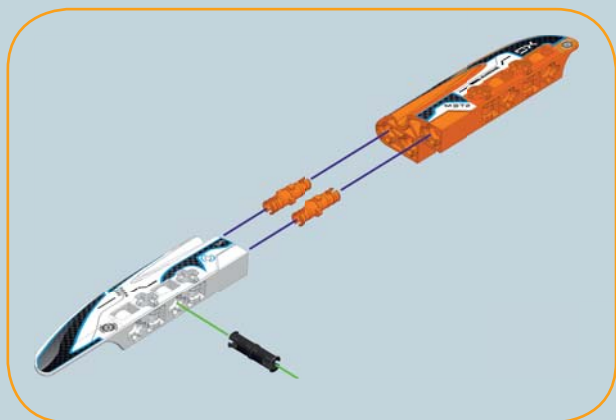
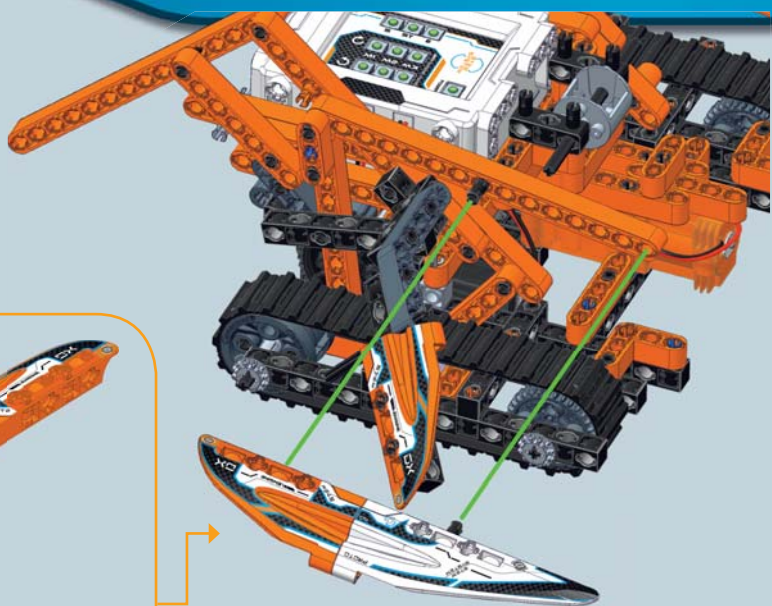
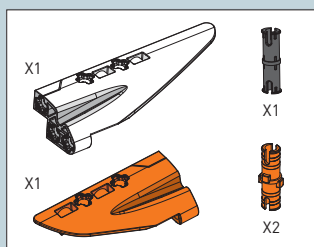


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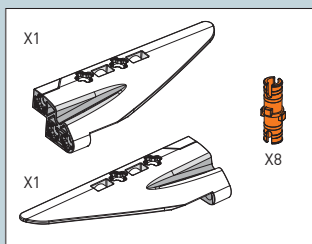
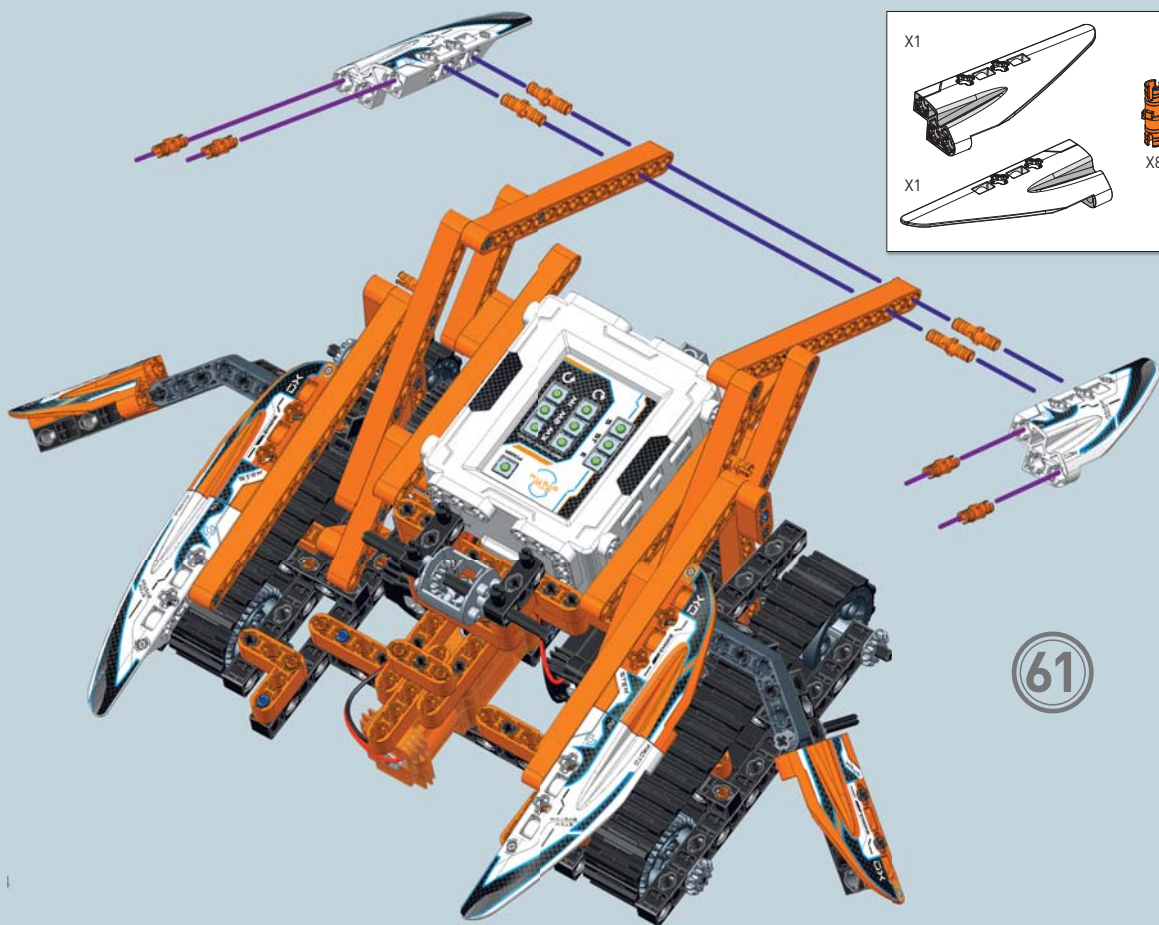


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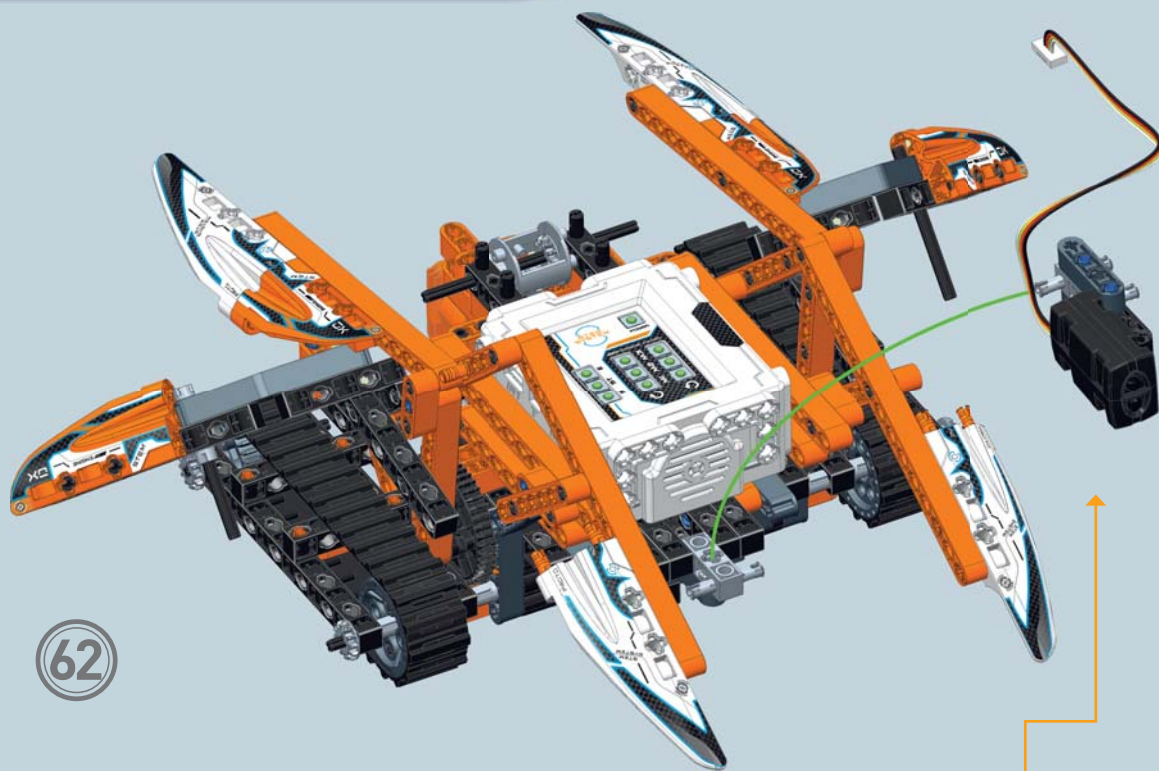




60



61



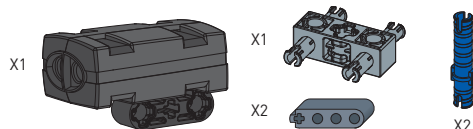
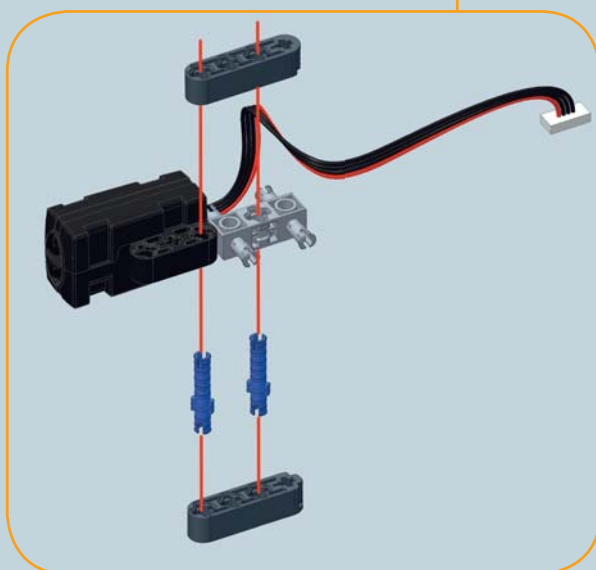
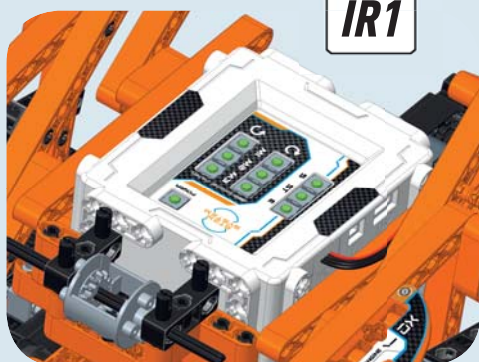
62

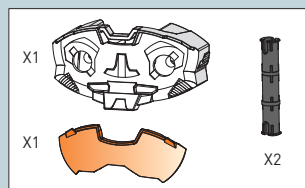
CONNECTE LE CAPTEUR AU MODULE CENTRAL

Connecte le capteur
IR au port IR1 du
module central

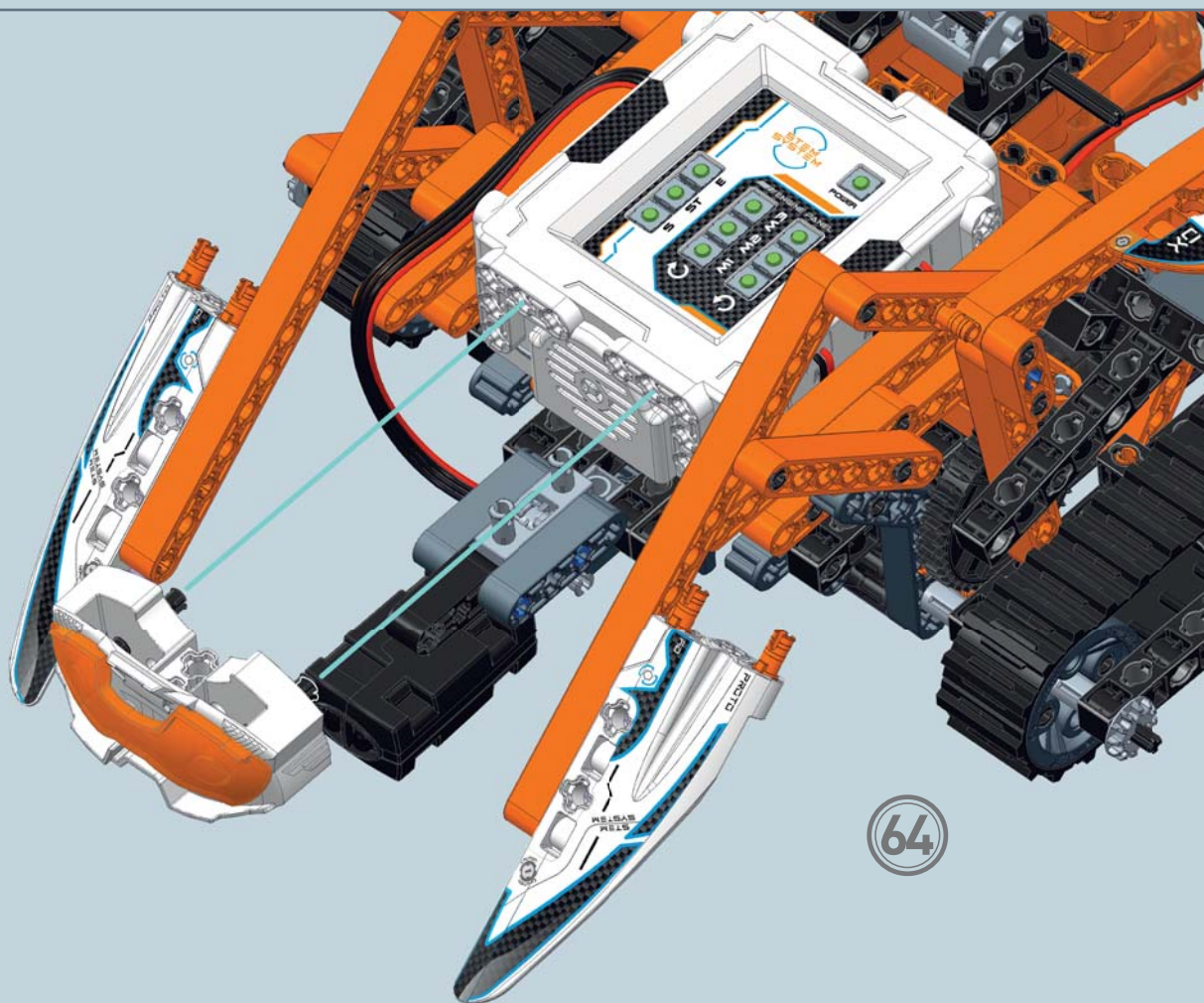
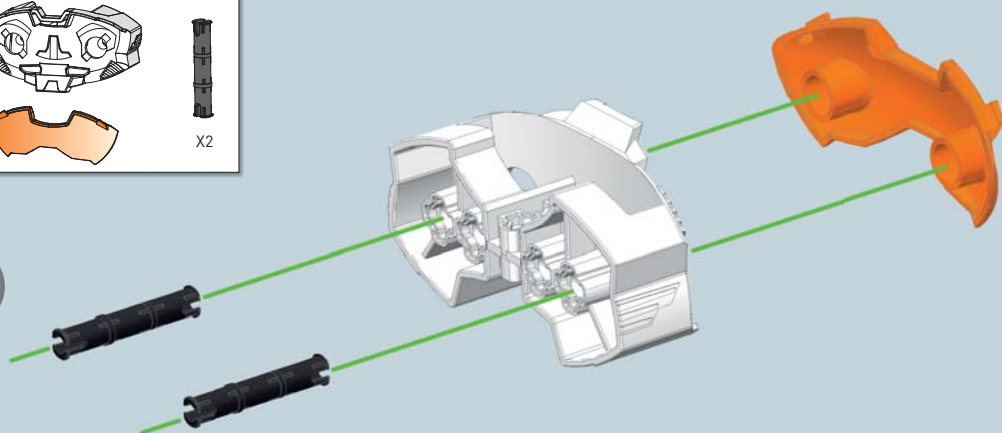


IR1



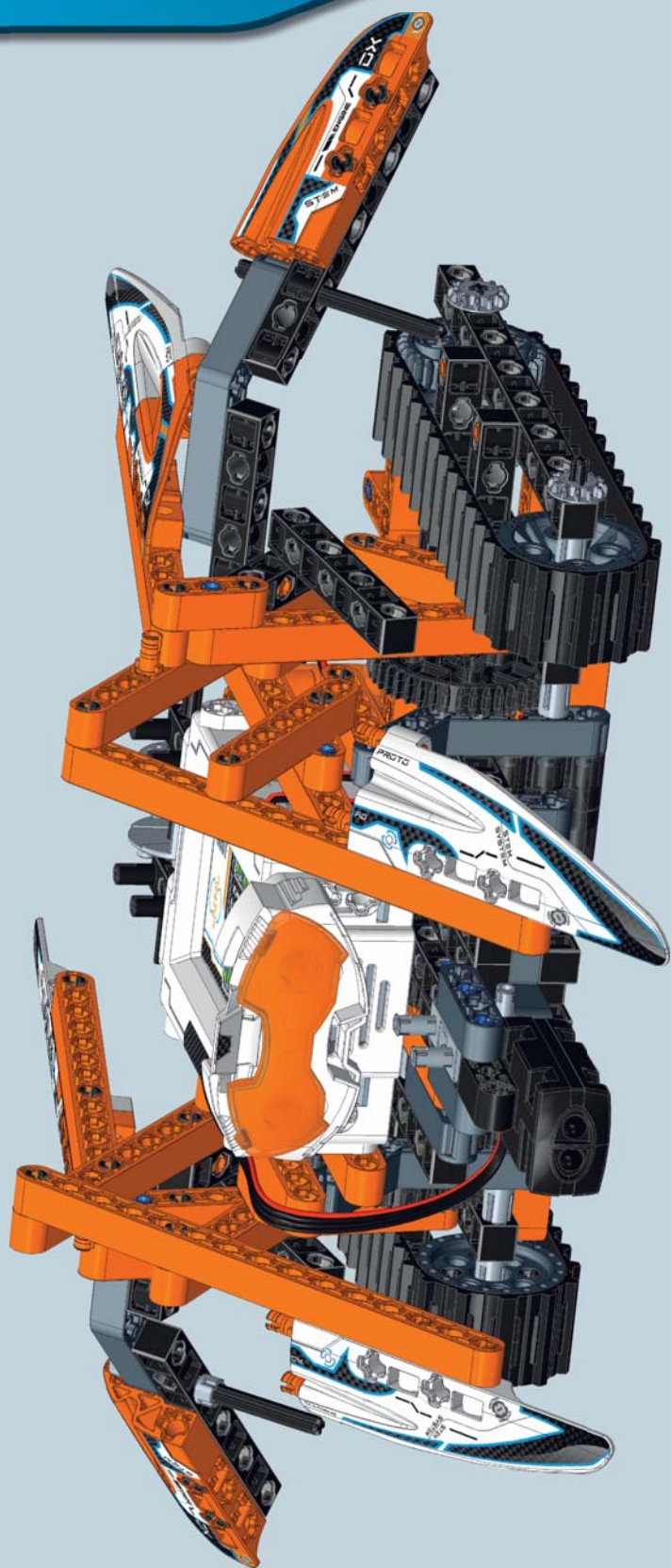


63



64

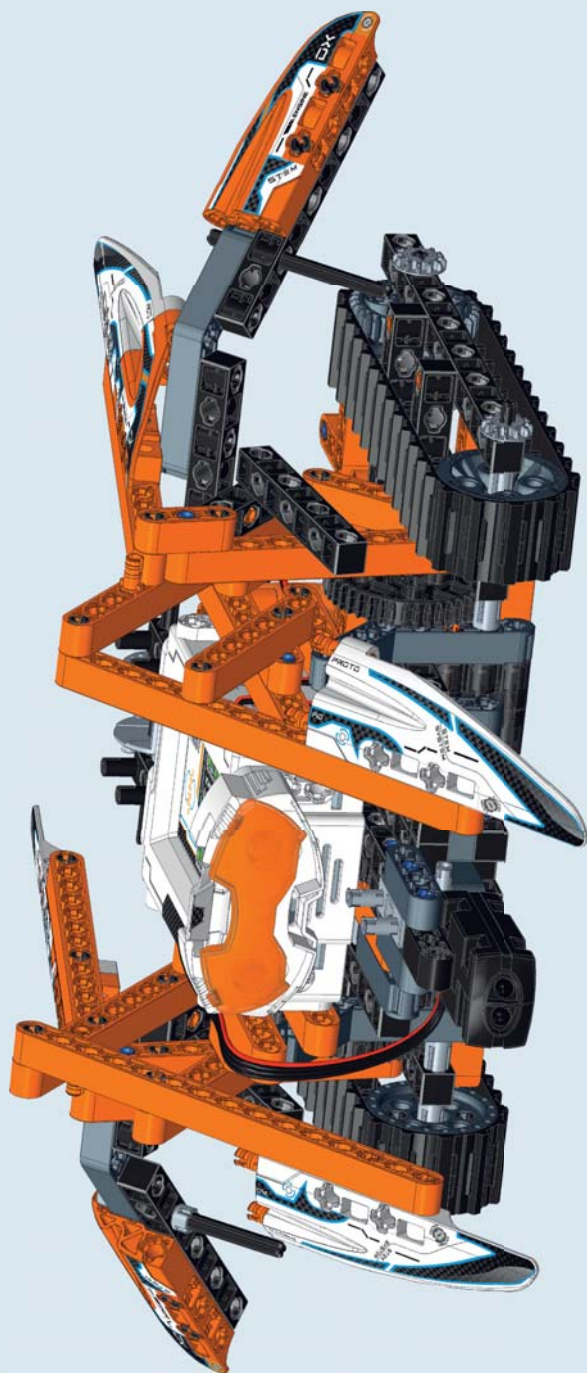
MODÈLE FINAL



Poursuis la proie !

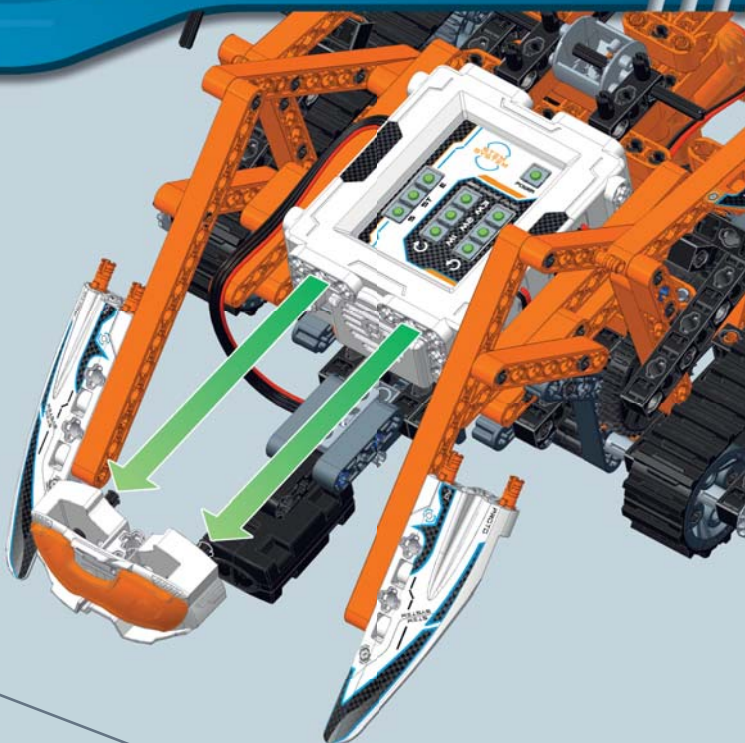
Assemblage

En partant du modèle final du robot proie, suis les instructions pour terminer le robot prédateur.

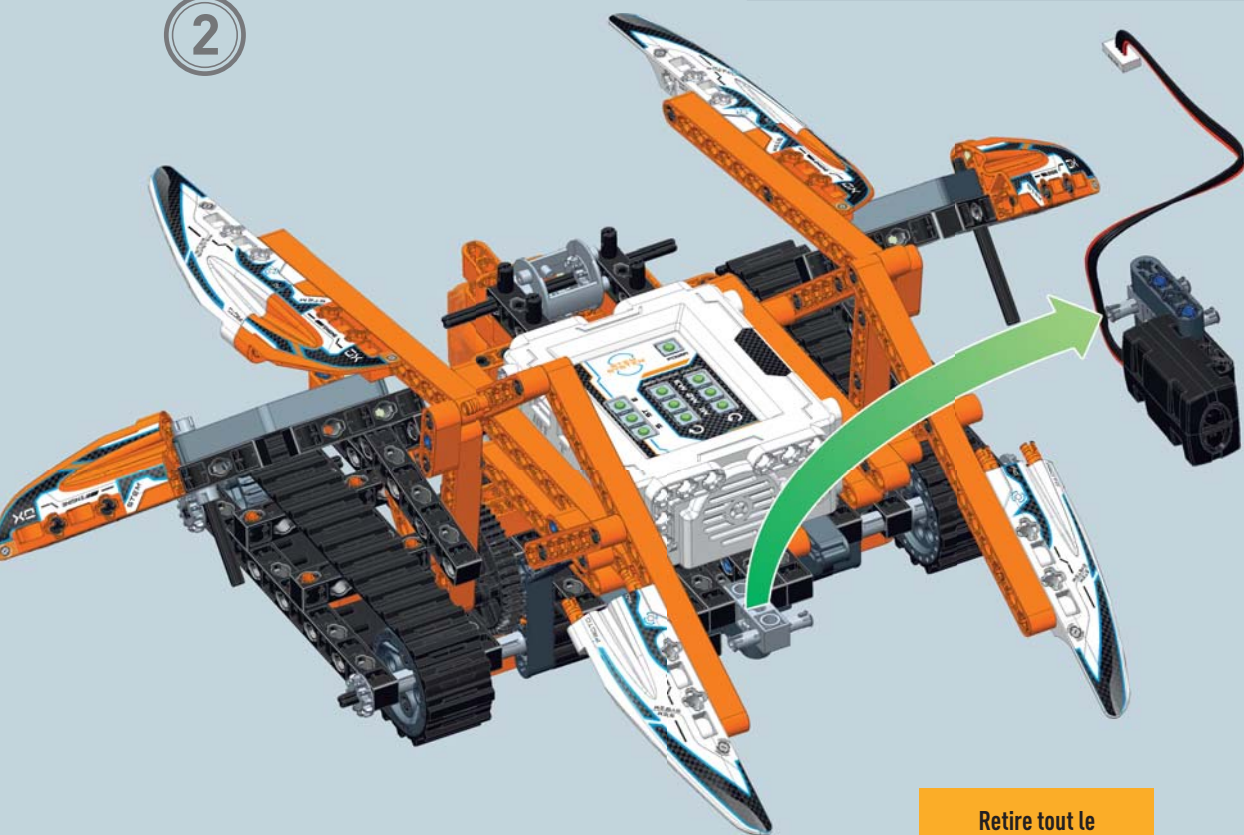


Retire le cache

1

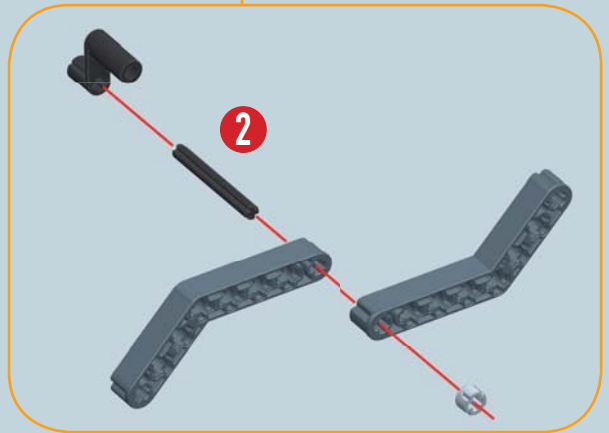
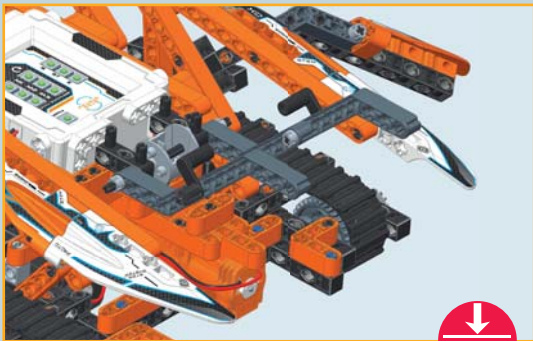
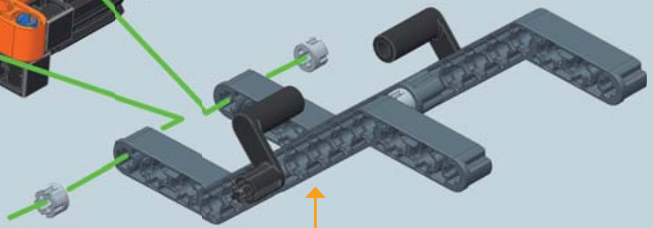
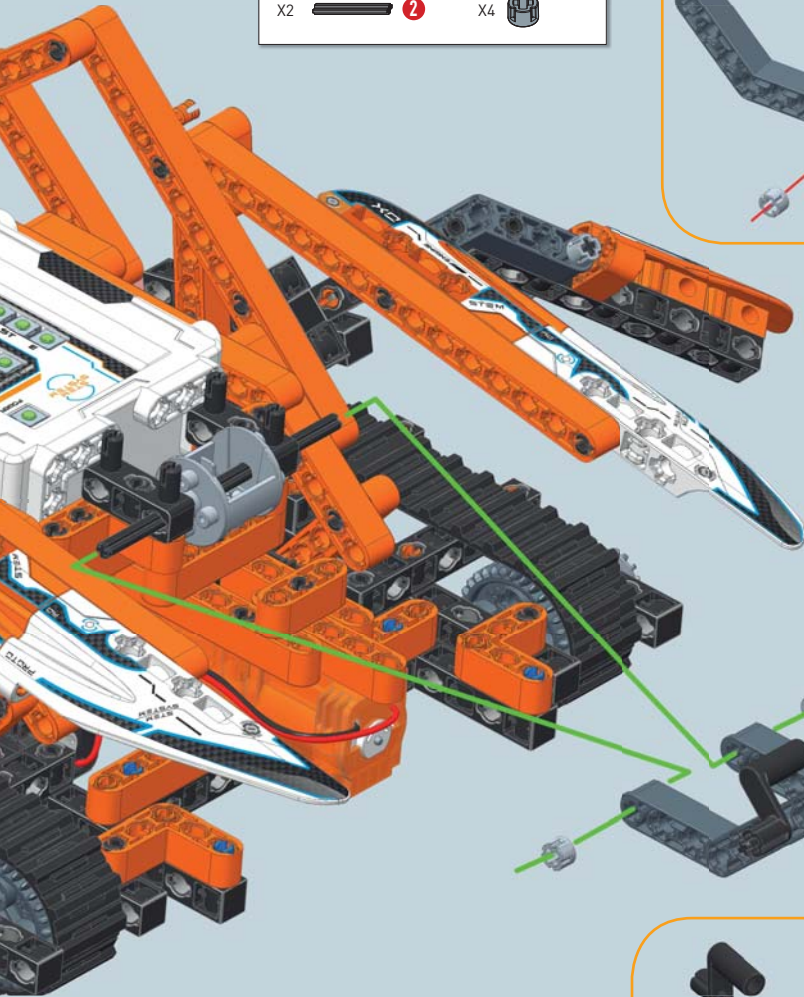
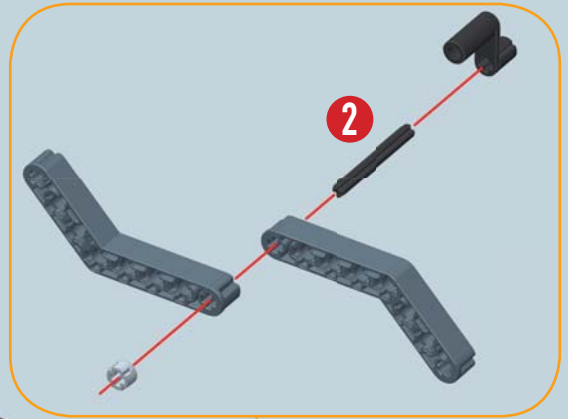
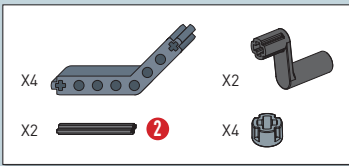


2



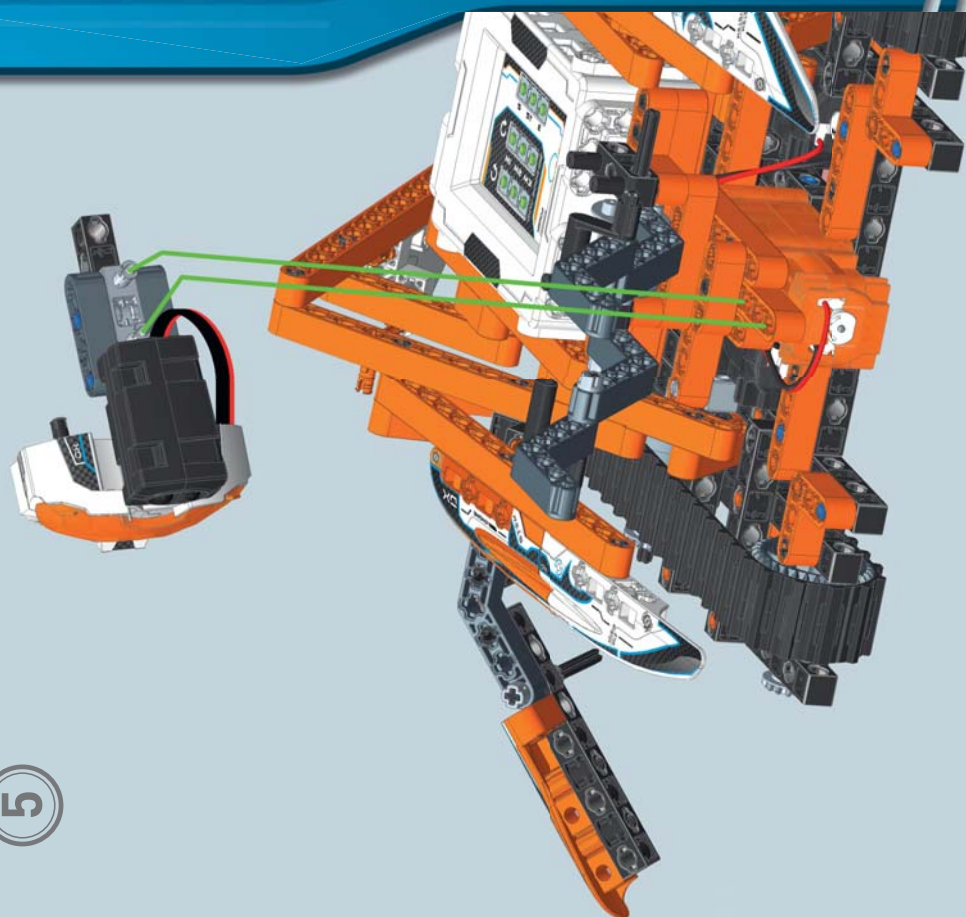
Retire tout le
bloc capteur

3

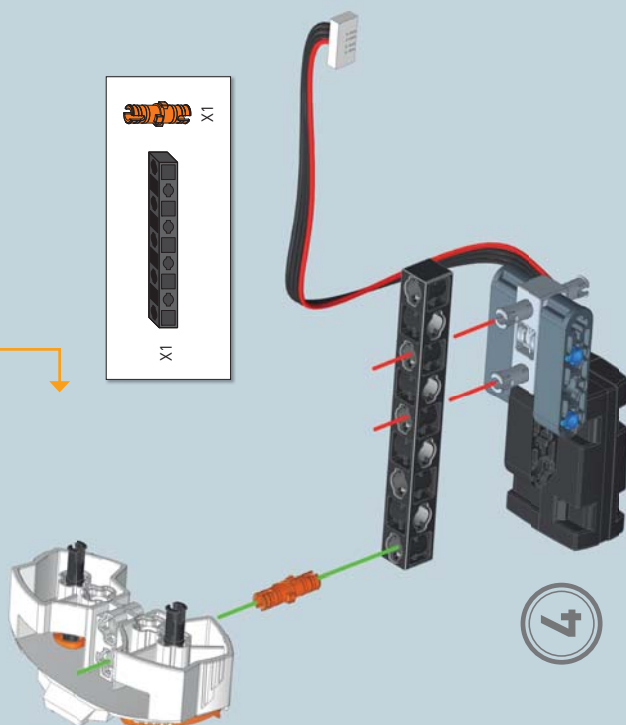


1:1

5



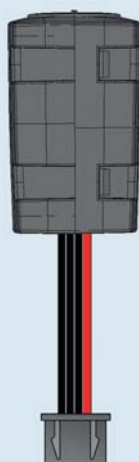
Change l'orientation du
visseur sur le cache.



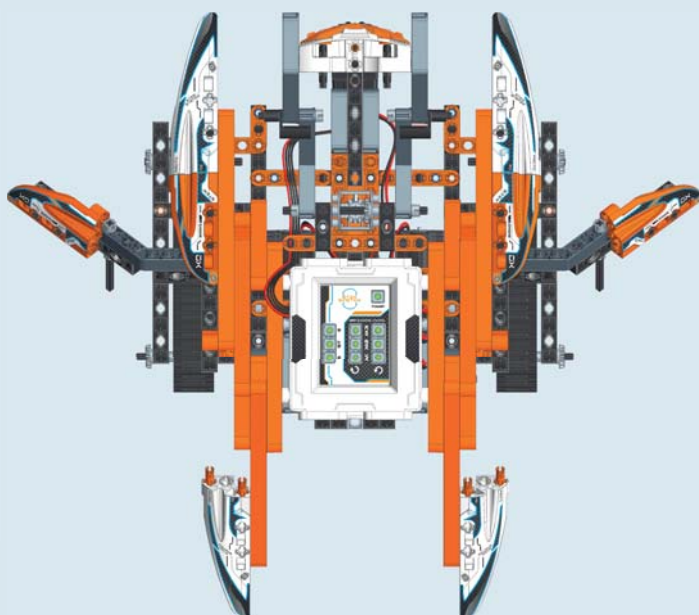
7

CONNECTE LE CAPTEUR AU MODULE CENTRAL

Connecte le capteur IR au port IR1 du module central.



IR1



MODÈLE FINAL

