

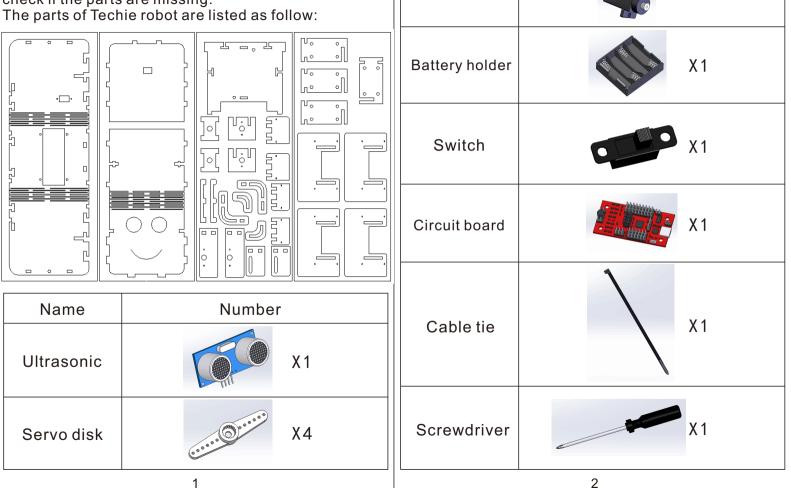
Techie Robot Assembly Instruction

Zhongshan Baijia Dagu Electronic Technology Co.,Ltd. Tel: 0760-22355466

©Baijiadagu.2018.08

Note

Please read instruction carefully before use and check if the parts are missing.

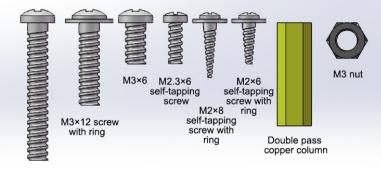


Servo

Χ4

Screw type:

Assembly of parts



M3×20

8pcs	2pcs	4pcs	4pcs 8pcs	10pcs	2pcs	10pcs
------	------	------	-----------	-------	------	-------

Installation note

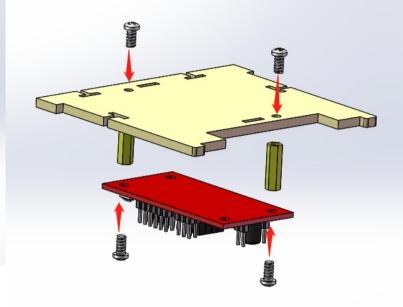
(1) The structure of the wooden board is fragile, and the structural position can be fixed without force. Please pay attention to the intensity during the installation process.

②After completing the assembly of each part, first connect the electronic components, open the switch to turn the servo angle to 90 degrees and then disconnect the wiring to star the overall assembly.

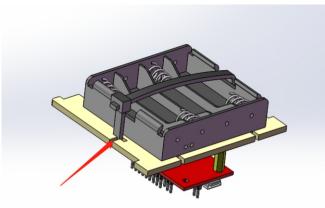
③battery selection

1. User need to assemble 4*AAA 3.2V lithium iron phosphate battery.

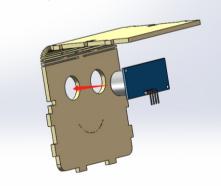
2. Directly convert the power supply to a 7.4V Li-polymer battery or a 7.4V lithium battery.



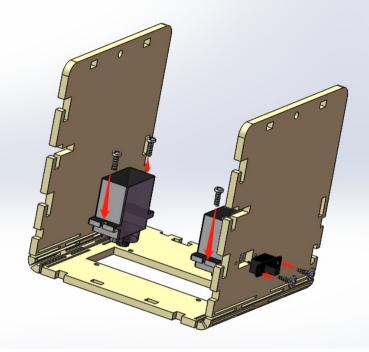
Step 1: Fix circuit board.



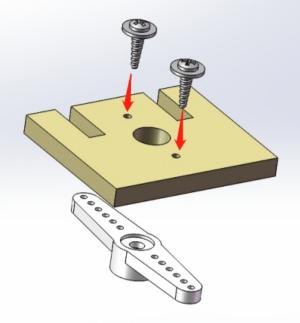
Step 2: Use a cable tie to fix the battery holder to the splint.

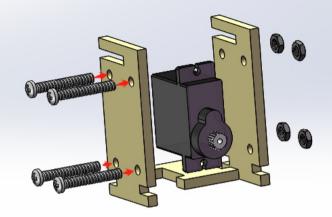


Step 3: Insert the ultrasonic into the eye position.



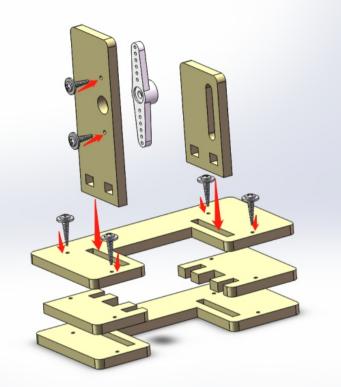
Step 4: Fix the two servos with M2.3 \times 6 self-tapping screws and switch with M2 \times 6 self-tapping screws with ring.





Step 5: Fix servo disk with M2 \times 6 self-tapping screws with ring.

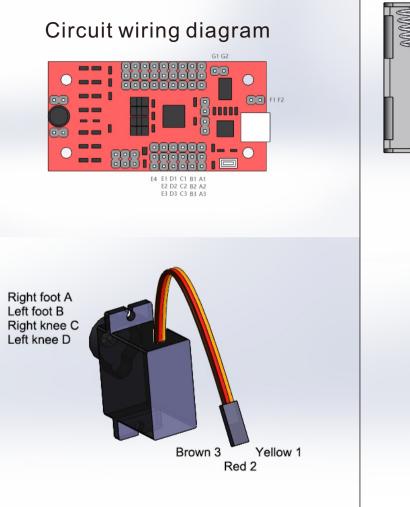
Step 6: Fix servo into legs with $M3 \times 20$ screws.

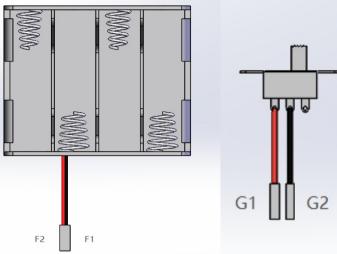


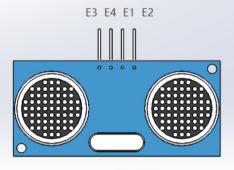
0000 I I E FJ

Step 7: The right foot plate: fix servo with M2 \times 6 self-tapping screws with ring and the foot plate with M2 \times 8 self-tapping screws with ring.

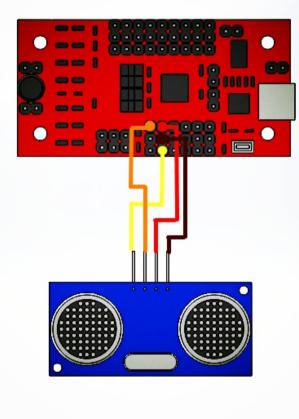
Step 8: The left foot plate: fix servo with M2×6 self-tapping screws with ring and the foot plate with M2×8 self-tapping screws with ring.

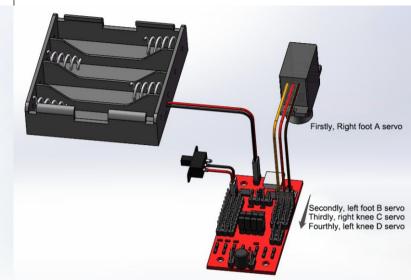






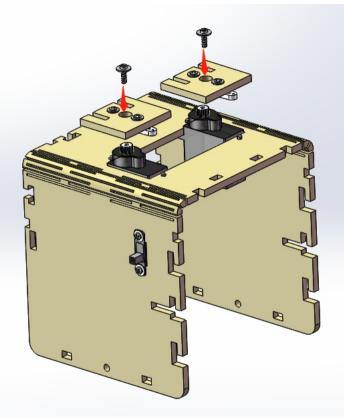
Partial wiring example diagram

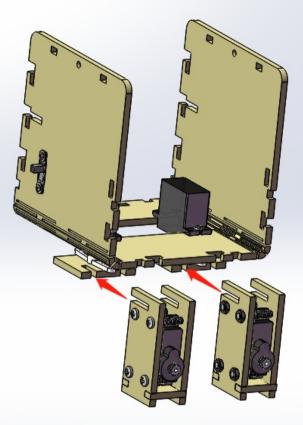




Note: Wiring first, then start the whole assembly See page 3 for detail.

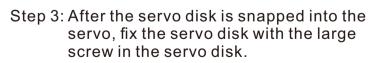
Overall assembly





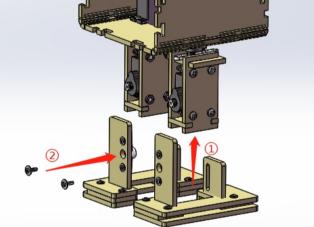
Step 1: Fix the joint position with the thicker screws in the servo bag.

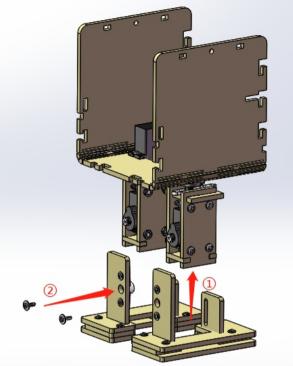
Step 2: Slightly loosen the leg screws before the legs snap into the joint position.

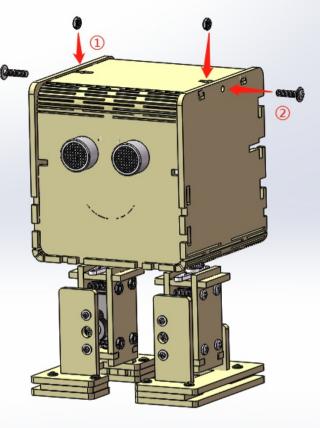


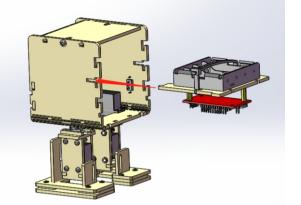
17

Step 4: Fix the face and lower plate with $M3 \times 12$ screws with ring and M3 nut.

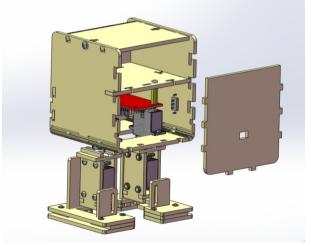




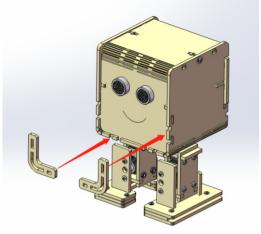




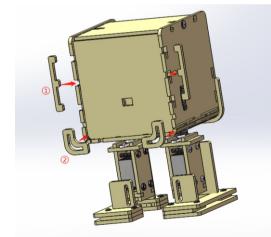
Step 5: Insert the middle splint into the head.



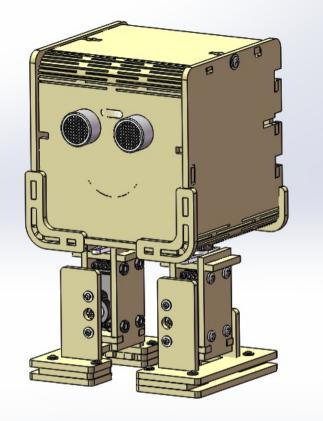
Step 6: Cover the back cover.



Step 7: Fit the front anti-drop fixed block.



Step 8: Fit the back anti-drop fixed block.



Step 9: Finished.

After connecting the motherboard to the computer, install the serial port driver CP2102USB2UART driverAddress: https://download.cs dn.net/download/wfysu/7957697

Step 1: Choose the arduino model.

File Edit Sketch					
	Auto Format	Ctrl+T			
	Archive Sketch				
testDance	Fix Encoding & Reload				
#include (Servo. 1	Serial Monitor	Ctrl+Shift+M			
#include @scills	Board	5		Arduino AVR Boards	
#include CEFROM. #include MoveFus	Processor			Arduino XVR Boards	
einclude Moveru		1			
int count=1;	Port	1		Arduino Yún Mini	
	Programmer			Arduino Industrial 101	
void setup() {	Burn Bootloader			linino One	
// put your setup	code here, to run once:			Arduino Uno WiFi	
Serial. begin (920	0);			Arduino Uno	
pinMode (AO, INPUT): // 定义超声波输入脚			Arduino Duemilanove or Diecimila	
	■); // 定义超声波输出脚			Arduino Nano	
get01dPosition(90	, 90, 90, 90);			Arduino Mega or Mega 2560	
				Arduino Mega ADK	
}				Arduino Leonardo ETH	
<pre>void loop() { delay(2);</pre>				Arduino Leonardo	
get01dPosition (90	00 00 00)			Arduino Micro	
	e here, to run repeatedly:			Arduino Esplora	
digitalWrite (A1, L				Arduino Espiora Arduino Mini	
	delayMicroseconds (2);			Arduino Mini Arduino Ethernet	
digitalWrite (A1, HIGH);					
del ayMi crose conds	(20);			Arduino Fio	
digitalWrite (A1, L	.OW);			Arduino BT	
float S=pulseIn (A	0, HIGH);			lilyPad Arduino USB	
S=S/58.00;				ilyPad Arduino	
if(S<10) count++;		•		Arduino Pro or Pro Mini	
if (count==9) coun switch (count) {	.t=1;			Arduino NG or older	
case 1: drunk(10	00) chroneler			Arduino Robot Control	
case 2:backyard				Arduino Robot Motor	
case 3:run (2, 10					
	Left (2, 1000); break;				
case 5: swing(2,					
case 6: goingUp ((700); break;				
case 7:noGravit					
case SikickLeft					
case 9:primera_	parte();break;				
1					
1					
4					
T		1-0.001		7 10/3/humi s/Wansi T/humus sost	
	nd in A. Mixiy Arduino Mix	190.991_min\arduin	10-1	.7.10\libraries\Nova: Library can't use both '	src and
'utility' folders.					

Step 2: Choose port.

💿 testDance Ardu	ino 1.7.10				x I
File Edit Sketch To					
File Edit Sketch II					_
		Ctrl+T			P
Levilla and	Archive Sketch				-
testDance	Fix Encoding & Reload				M
#include (Servo. 1	Serial Monitor	Ctrl+Shift+M			-
#include <0scill:					
#include < EEPROM.	Board	,			
#include "MoveFu	Processor	,			
	Port		Serial ports		
int count=1;			COM1		
	Programmer	,	✓ COM3		
void setup() {	Burn Bootloader		•		
	o code here, to run once:				
Serial. begin (920					
	1); // 定义超声波输入脚				
	Π); // 定义超声波输出脚				
get01dPosition (90), 90, 90, 90) ;				
}					
void loop () {					
delay (2);					
get01dPosition (90					
	le here, to run repeatedly:				
digital⊮rite(A1, I					1
delayMicroseconds					
digitalWrite(A1,)					
delayMicroseconds					
digitalWrite(A1, I					
float S=pulseIn()	(O, HIGH):				
S=S/58.00;					
if(S<10) count++;					
if(count==9) cour	st=1;				
switch (count) {					
case 1: drunk (10					
	1(2, 1000); break;				
case 3:run (2, 10	deft (2, 1000); break;				
case 5: swing (2,					
case 6:goingUp case 7:noGravit					
case S:kickLeft					
case 9:primera					
cuse o.primera_	parte(), oreax,				
, '					
<i>'</i>					-
٠					F.
	nd in H:\Mixly_Arduino\Mixl	y0.991_win\ard	uino-1.7.10\libraries\Nov	a: Library can't use both 'src' a	nd
'utility' folders.					
					-
				o or Pro Mini, ATmega328 (5V, 16 MHz) or	

Step 3: Click the right arrow to burn the written program into the board.

💿 testDance Arduino 1.7.10	
File Edit Sketch Tools Help	
🗸 📀 🌆 🎦 Upload	Q
testDance	
#include (Servo. h)	
#include (Oscillator.h)	
#include (EEPROM. h)	
#include "MoveFunction.h"	
int count=1;	
void setup() {	
// put your setup code here, to run once:	
Serial. begin (9200);	
pinMode(AO, INPUT): // 定义超声波输入脚	
pinMode(A1, OUTPUT): // 定义超声波输出脚	
get01dPosition(90, 90, 90, 90);	
}	
void loop() {	
delay(2);	
get01dPosition (90, 90, 90, 90);	
//put your main code here, to run repeatedly:	
digitalWrite(A1, LOW);	
del ayMicroseconds (2);	
digitalWrite(A1, MIGH);	
del ayMicroseconds (20):	
digitalWrite(A1, LOW);	
float S=pulseIn (AD, HIGH);	
S=S/58.00;	
if(S<10) count++;	
if(count==9) count=1;	
switch (count) (
case 1: drunk (1000); break;	
case 2: backyard (2, 1000); break;	
case 3:run (2, 1000); break;	
case 4:moonWalkLeft (2,1000);break:	
case 5: swing (2, 1000); break;	
<pre>case 6:goingUp (700); break; case 7:noGravity (800); break;</pre>	
case /:nowrawity(800);break; case 8:kickLeft(900);break;	
case 9: primera_parte(); break;	
case S. primera_parte(); break;	
}	
<	•

Arduino Pro or Pro Mini, ATmega328 (5V, 16 MHz) on COM3

A program case



Mixly graphical programing case

	and storige and persons and			
a Blocks	Code	Copyright © MixCy Team@NEU HTTP://HDE27.04G	formal Advanced	in (" Keglich -
In/Out	DigitalN-Ite PINe 1 45 * Stat 8 LOW *	setup		
₽% Control	0+1+/ (MMR 0 2	Service and some state (1200)		
🕝 Math	Digitalerite FINE DAL * Stat B HIGH *	pistude (Ad - Stat Exerting		
T Text	Delay (2010 1 20	plantade () AL - Stat COTOUTIO		
Lists	DigitalM-ite FINE (AL + Stat) LON -	getüldistition Alghtfort 77 Leftfort 70 KightLeg 78 Lefting 79		
Logic	B pulsels(ps) file (Ar + state (2001)	Bertane Count an Entill value : 2		
/ SerialPort		_		
🗶 Communicate				
a sensor				
Actuator	0 1 (Count CO () + (Count C)			<
Monitor	maitch (court)			
√ variables	Ca10 10			
Punctions	cese			
Techie				0 D.
New Open Save	Save as Export Import Manager		Compile Upload Adamo Pro or Pro Mine, - COM1 -	Murator O
the second s				the second se

Techie robot video:

Link: https://www.dropbox.com/sh/nhd41t5wzcsn71z/AADSd sDI0ho-KUSM37QqznPxa?dl=0