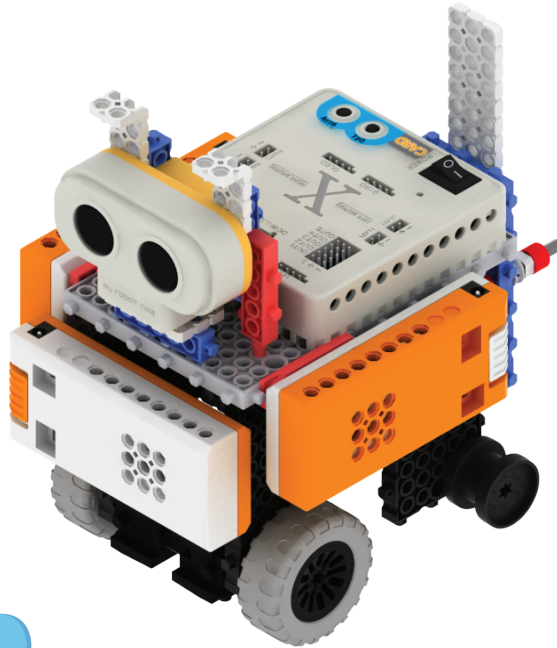
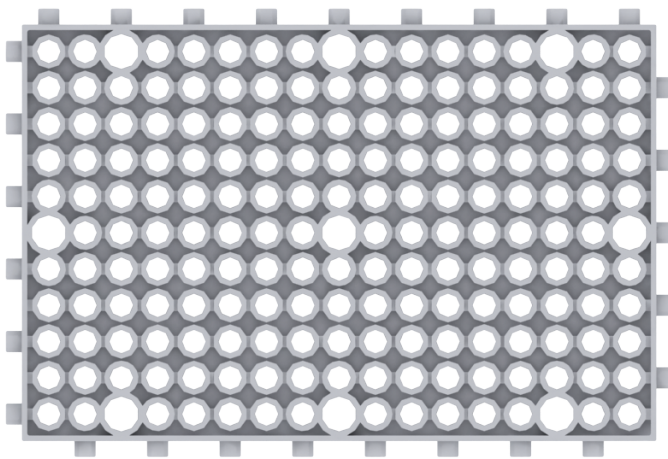




# 33 Perro robot



## Piezas



Bloque 11x17 (1)



Adaptador L 2x4 (2)



Bloque N 1x7 (1)



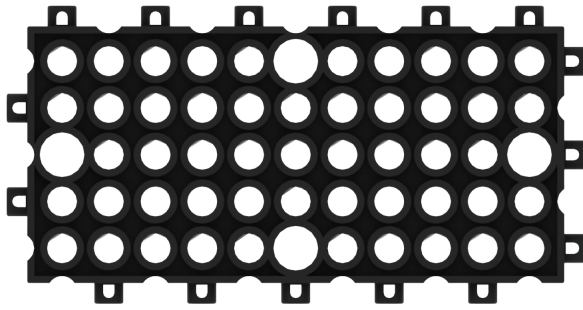
Bloque N 3x9 (3)



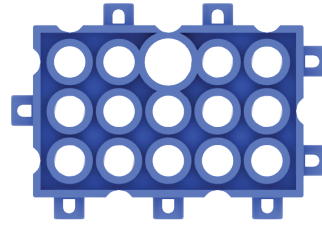
Bloque N 3x5 (1)



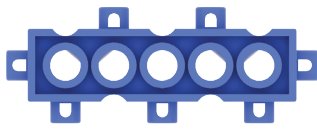
Bloque N 1x5 (1)



Bloque 5x11 (4)



Bloque 3x5 (1)



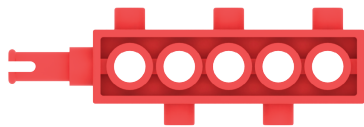
Bloque 1x5 (6)



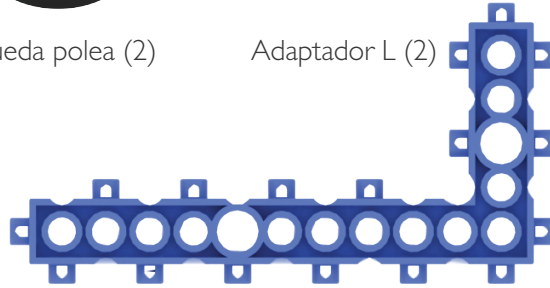
Rueda polea (2)



Adaptador L (2)



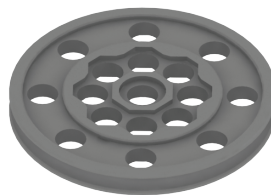
Bloque con eje (2)



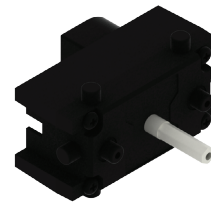
Bloque 90° (1)



Rueda M (2)



Llanta 2 (1)



Motor 2 (2)



Conector de eje (2)



Goma de eje roja (2)



Arandela (4)



Eje S (1)



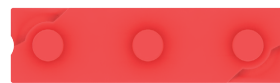
Remache básico (7)



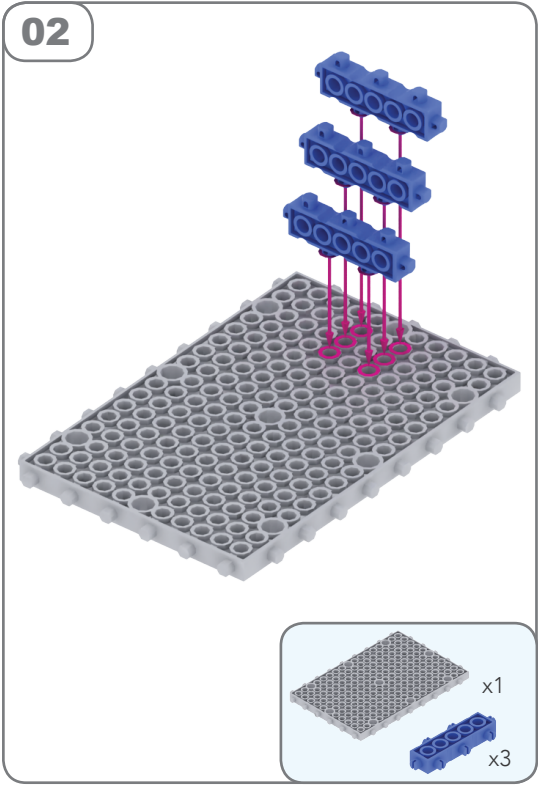
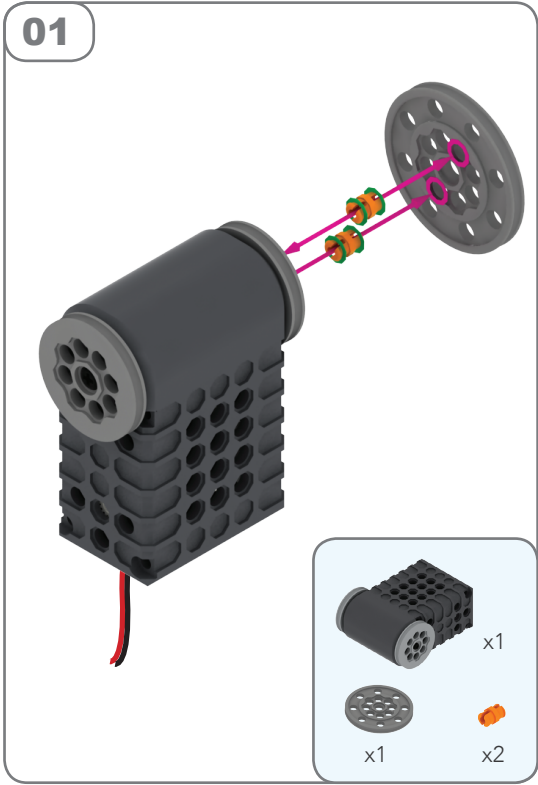
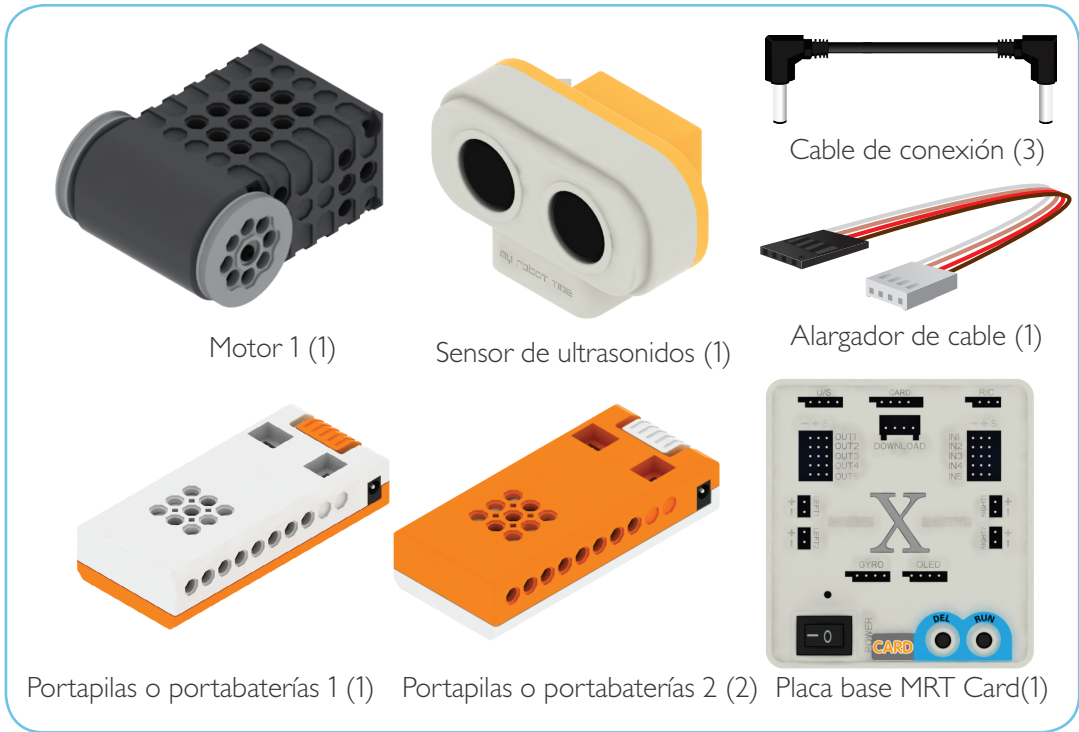
Remache S (1)



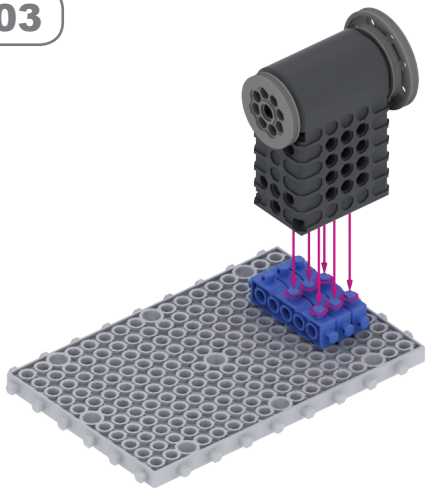
Remache L (3)



Bloque de unión 1 (2)

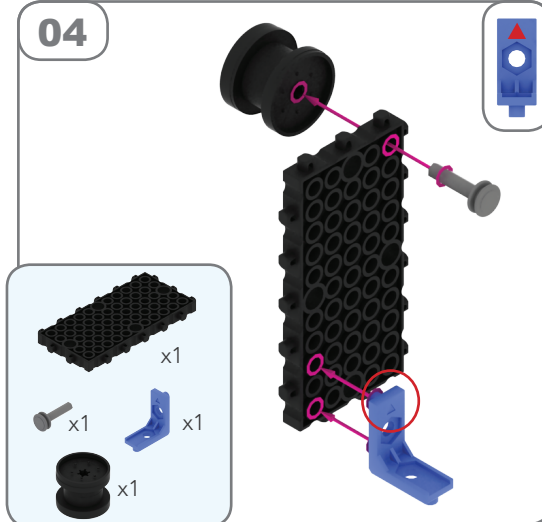


03



Nota: el triángulo rojo ▲ señala la posición.

04

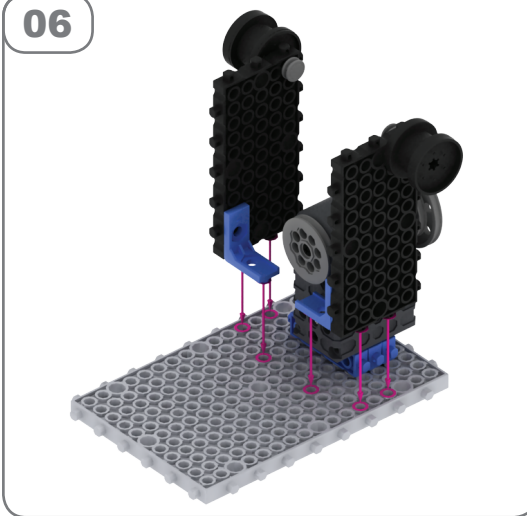


05

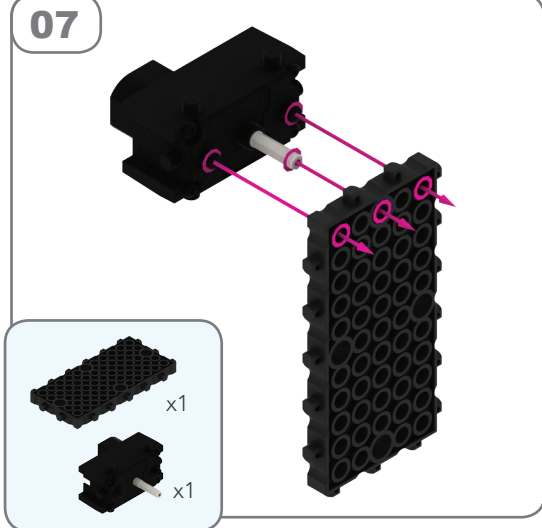


Nota: el triángulo rojo ▲  
 señala la posición.

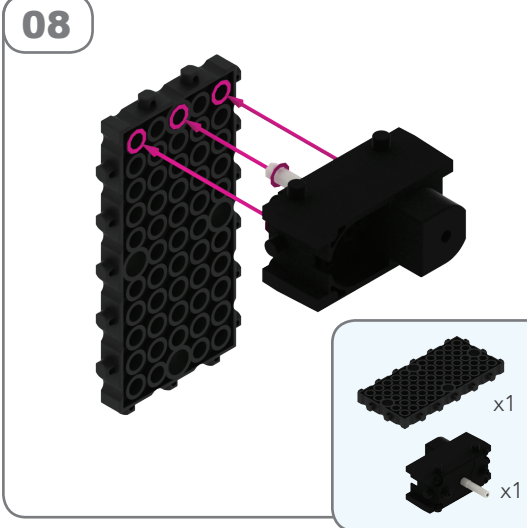
06



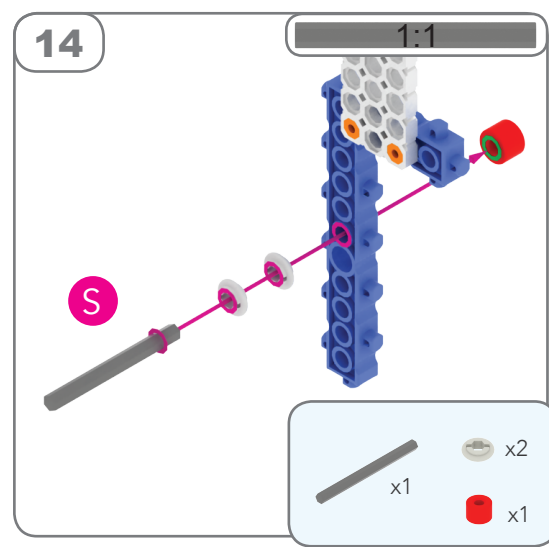
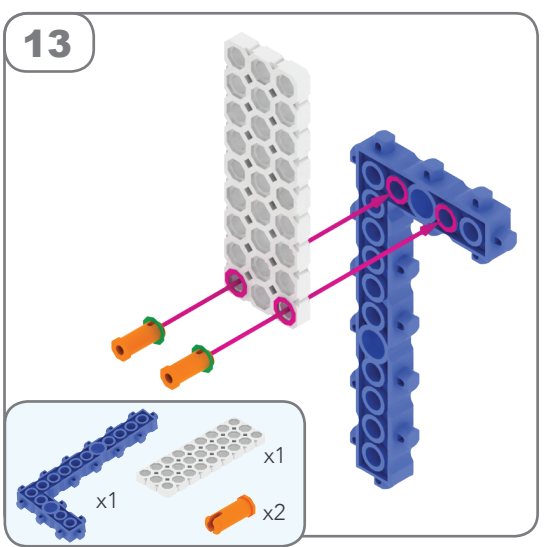
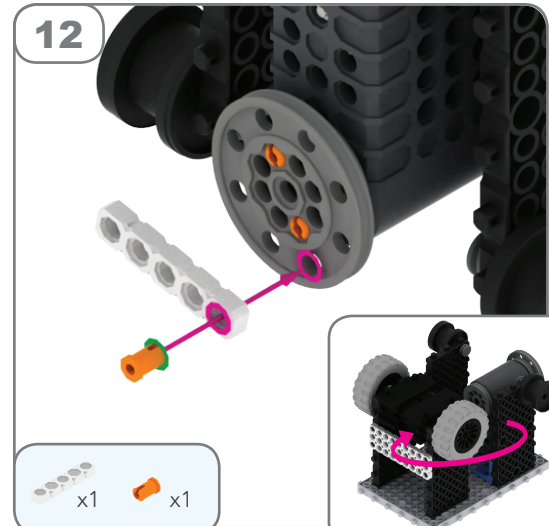
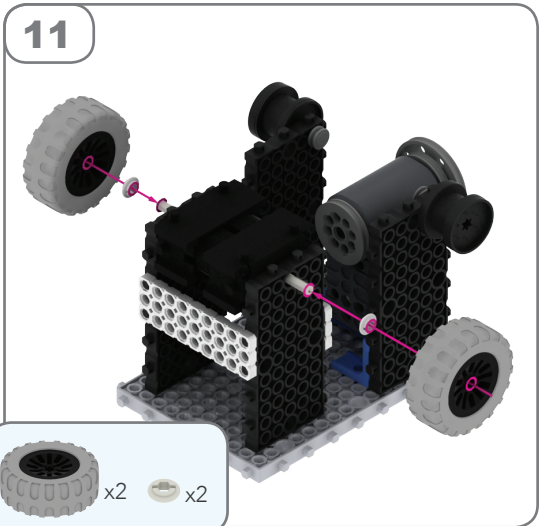
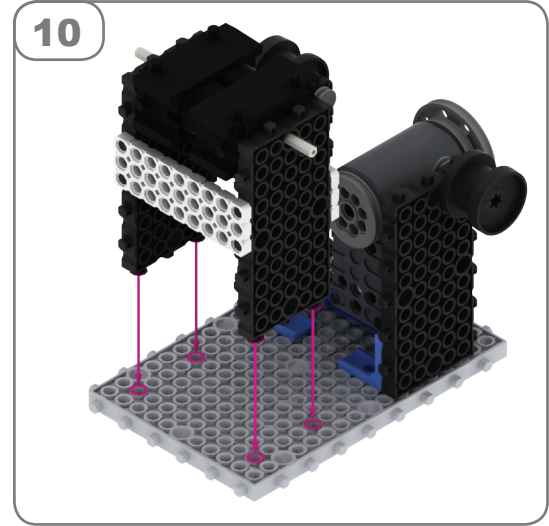
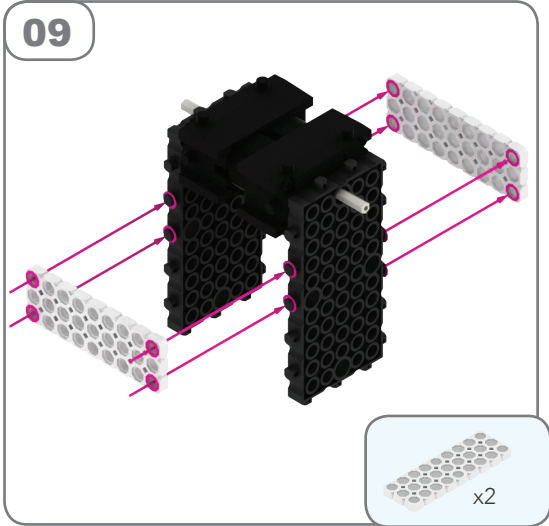
07

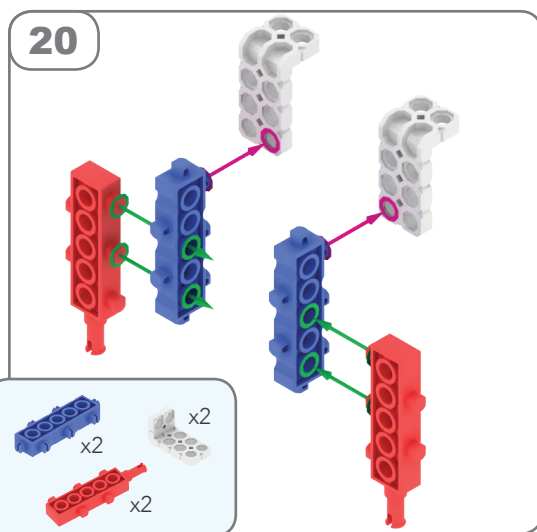
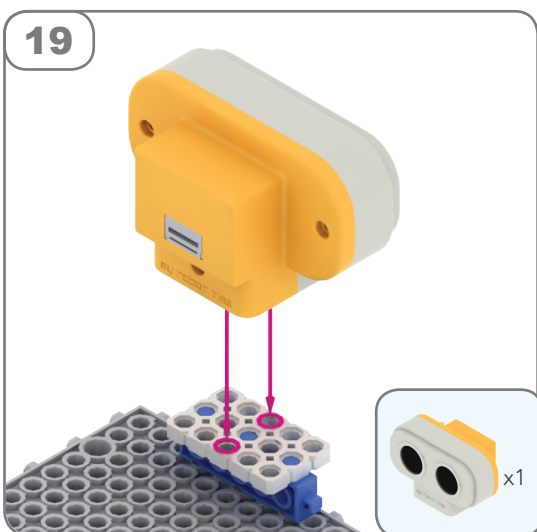
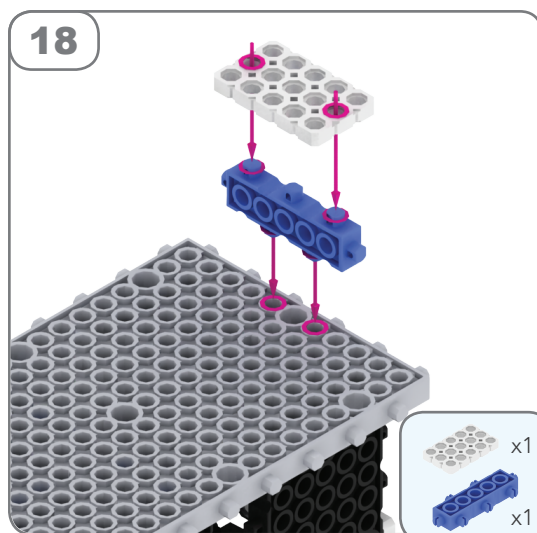
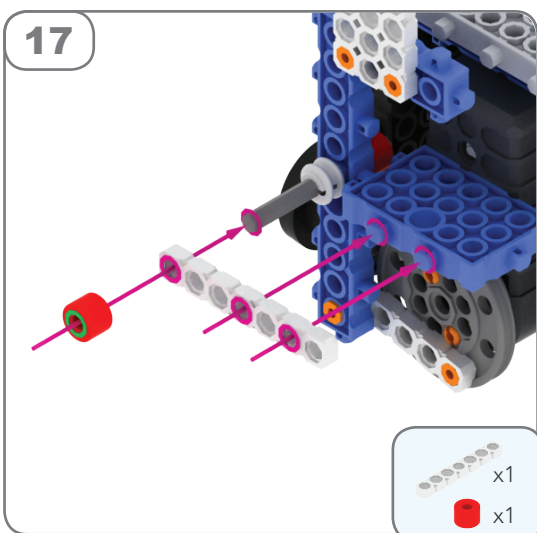
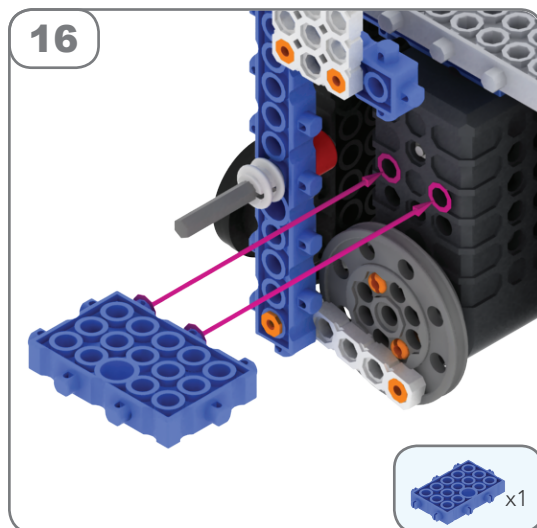
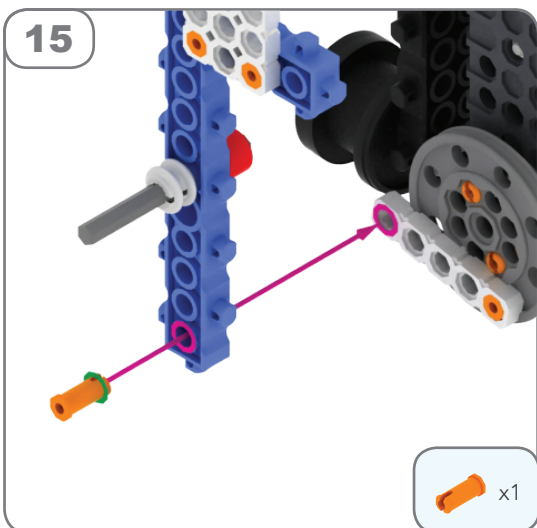


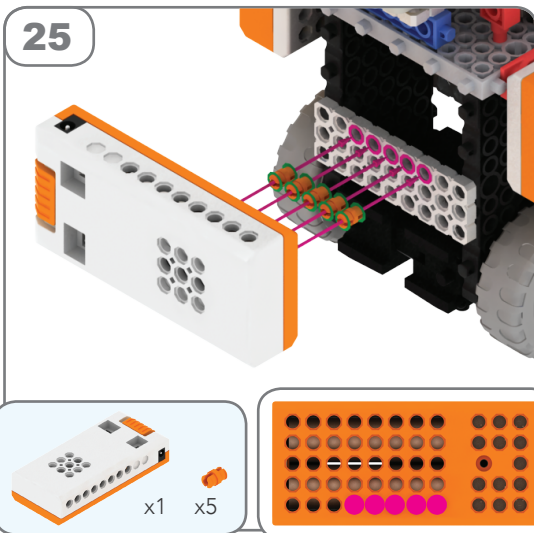
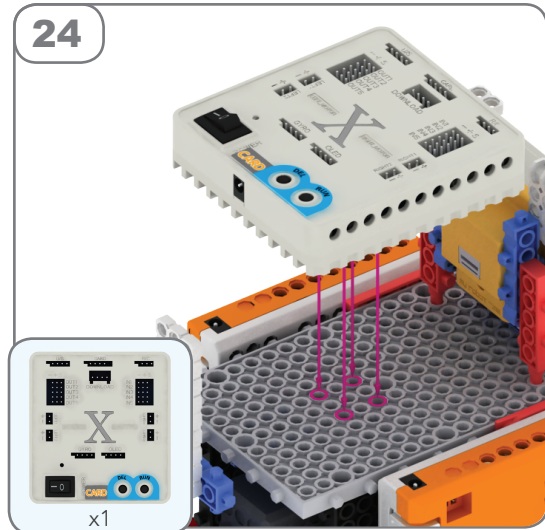
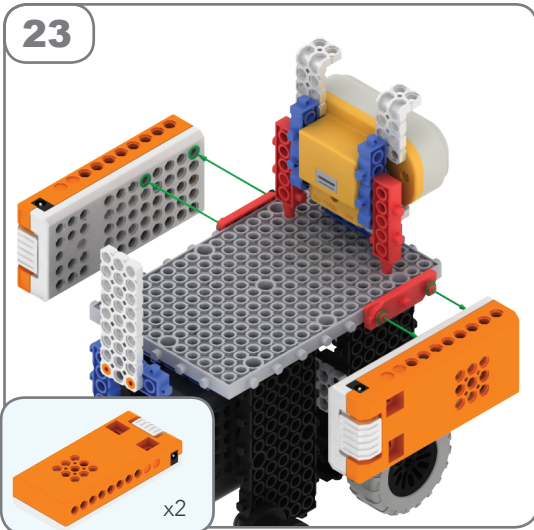
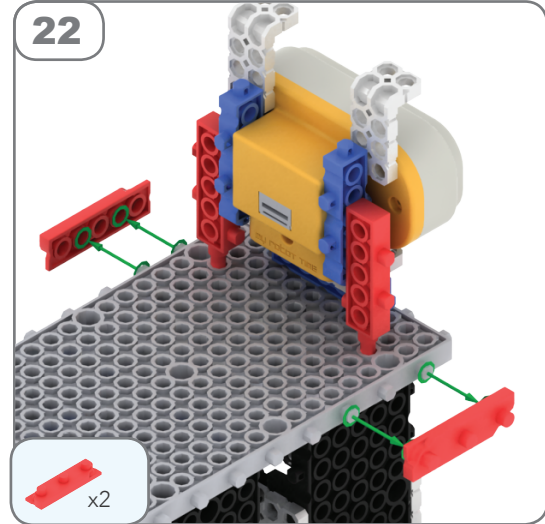
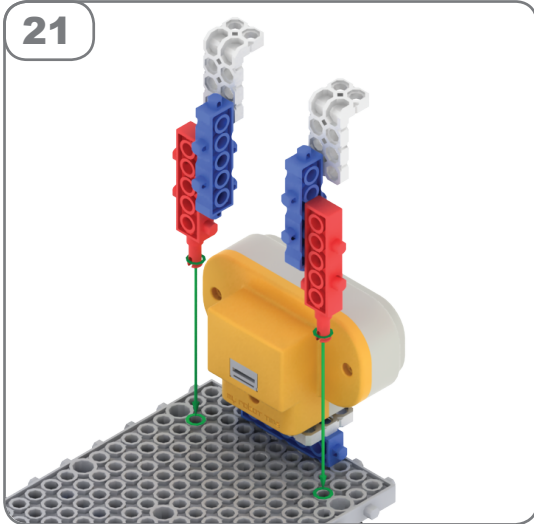
08









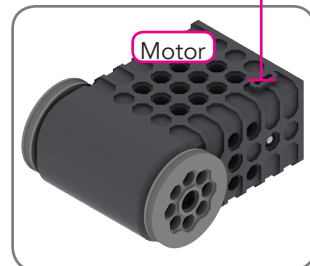
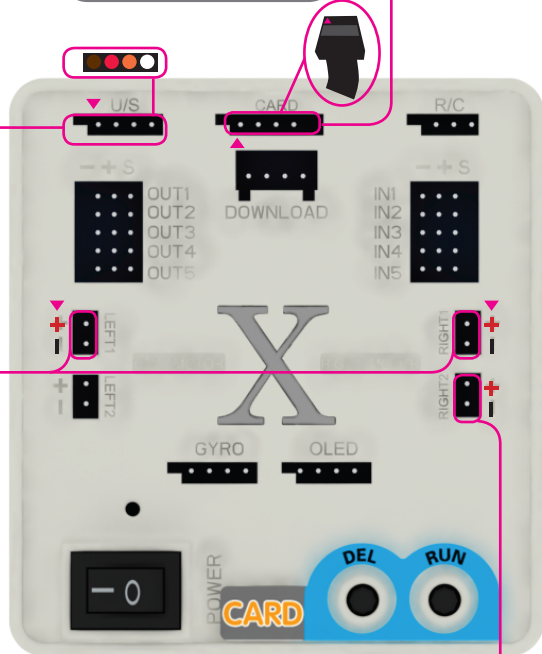
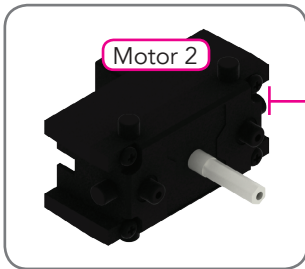




## ¿Cómo hacer la conexión?



Haz que el ▲ se corresponda con el ▲ del conector del cable del lector de tarjetas





Practica



0



Detect distance 2cm-10cm



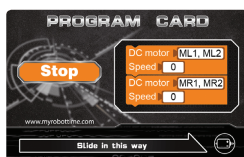
Detect distance 10cm-50cm



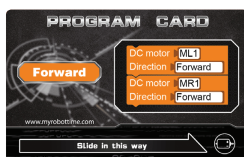
Delay 1 sec



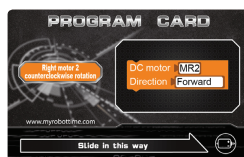
Detect distance 50cm-100cm



Stop



Forward



Right motor 2 counterclockwise rotation



Cycle start (all time)



Cycle end

Programación:

1. Cycle start(all time)
2. Detect distance 50cm-100cm
3. Stop
4. Detect distance 10cm-50cm
5. Forward
6. Delay 1 sec
7. Stop
8. Detect distance 2cm-10cm
9. Right motor 2 counterclockwise rotation
10. Cycle end