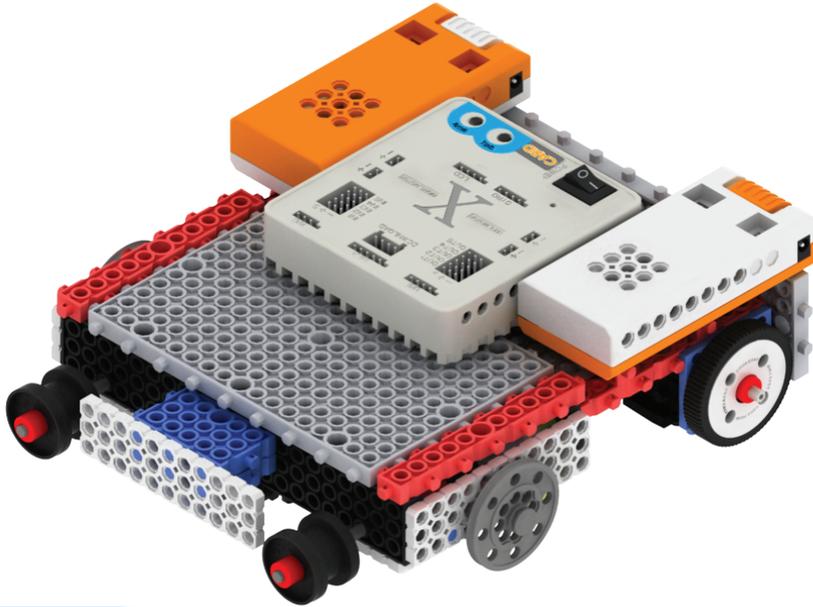
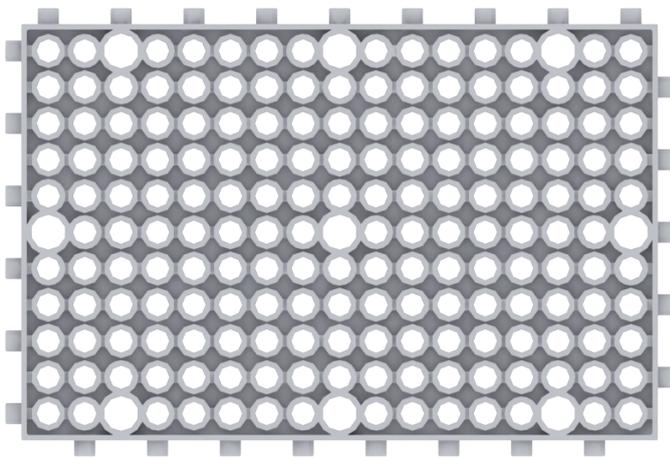




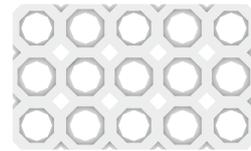
13 Coche de choque



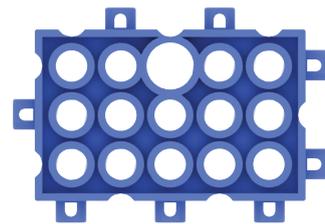
Piezas



Bloque 11x17 (2)



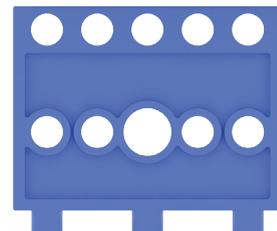
Bloque N 3x5 (2)



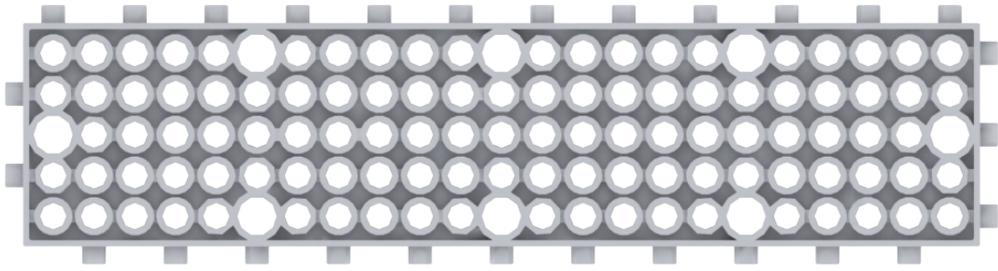
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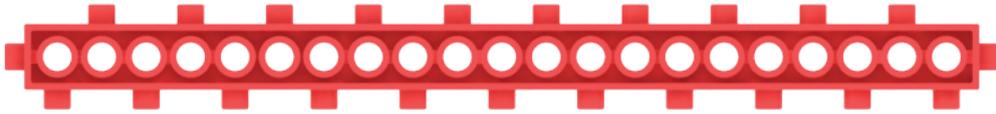
Bloque N 3x11 (3)



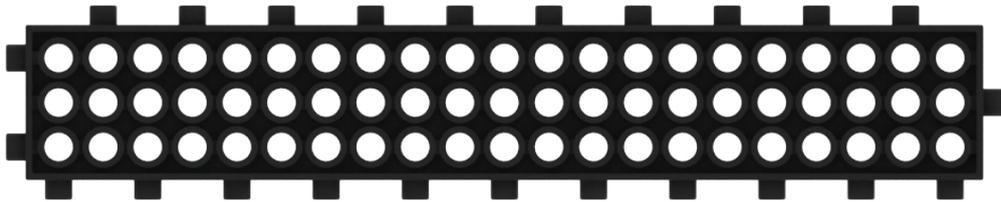
Soporte de motor (2)



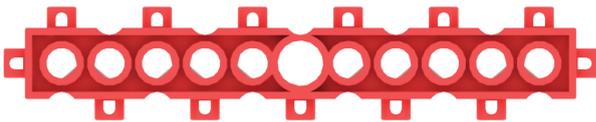
Bloque 5x23 (1)



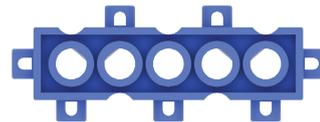
Bloque 1x21 (2)



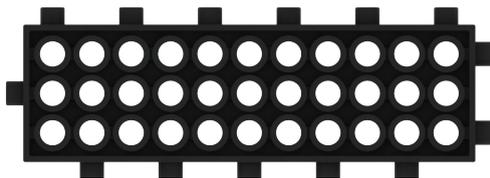
Bloque 3x21 (2)



Bloque 1x11 (4)



Bloque 1x5 (2)



Bloque 3x11 (1)



Adaptador L (2)



Rueda polea/
Guide wheel (2)



Conector de eje (2)



Goma de eje roja/Red bush (10)



Eje L (2)



Unión de ejes (2)



Arandela (2)



Llanta/Hub 2 (2)



Rueda S (2)



Sensor pulsador (2)



Motor 2 (2)



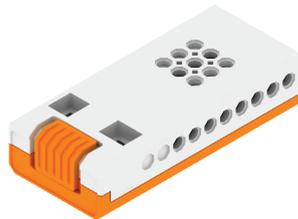
Cable de conexión (2)



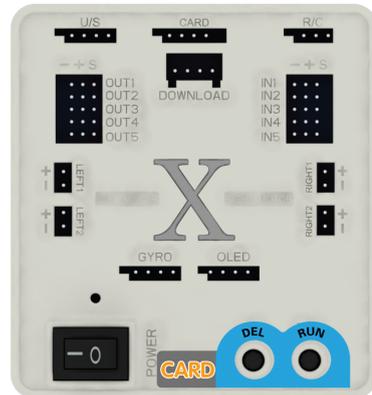
Alargador de cable (2)



Portapilas o portabaterías 1 (1)

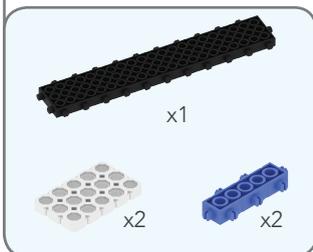
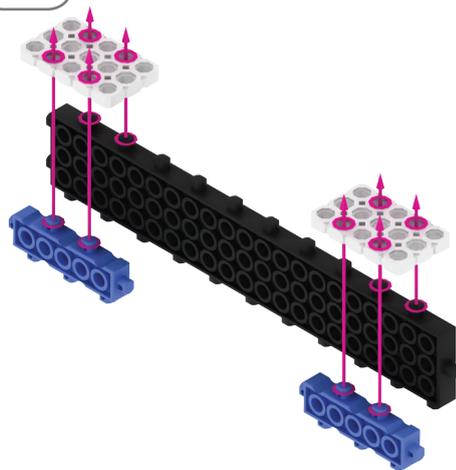


Portapilas o portabaterías 2 (1)

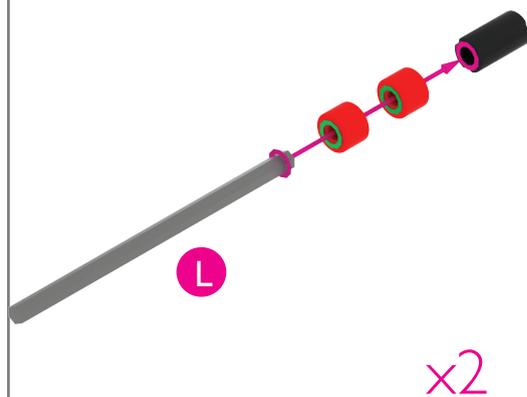


Placa base (1)

01



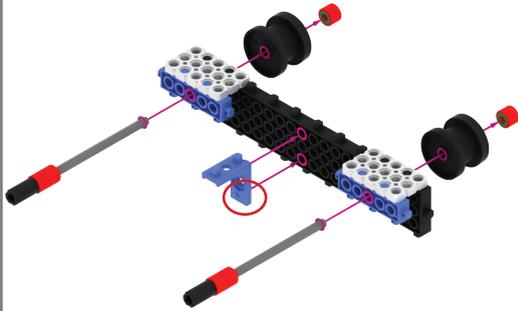
02



1:1

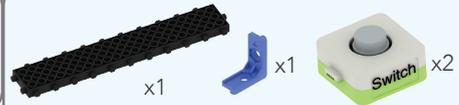
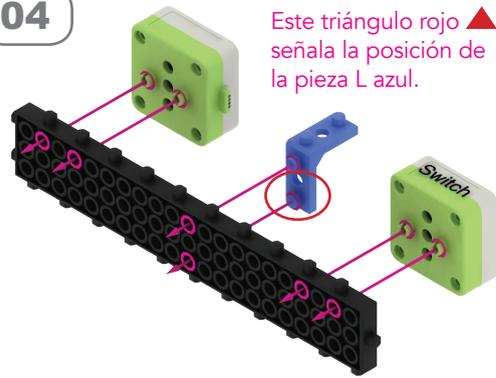
03

Este triángulo rojo ▲ señala la posición de la pieza L azul.

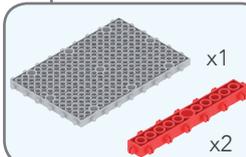
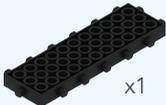
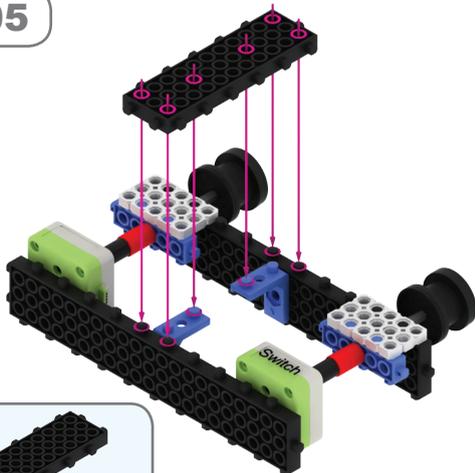


04

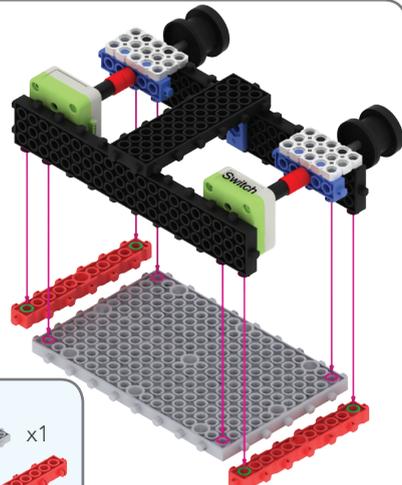
Este triángulo rojo ▲ señala la posición de la pieza L azul.



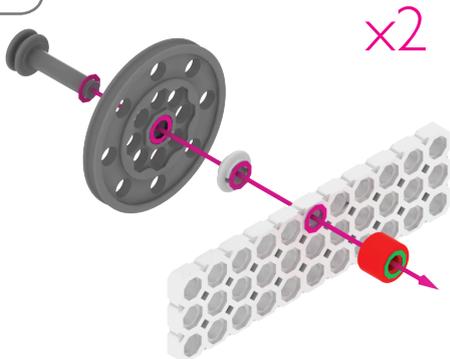
05



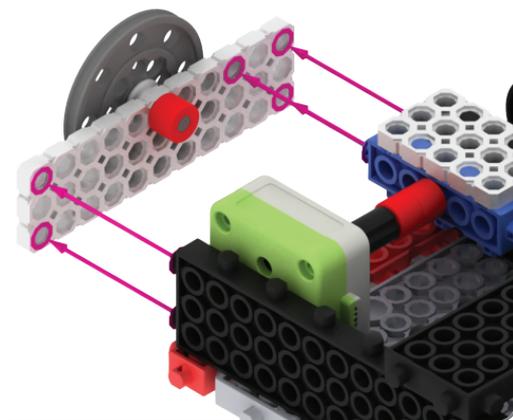
06

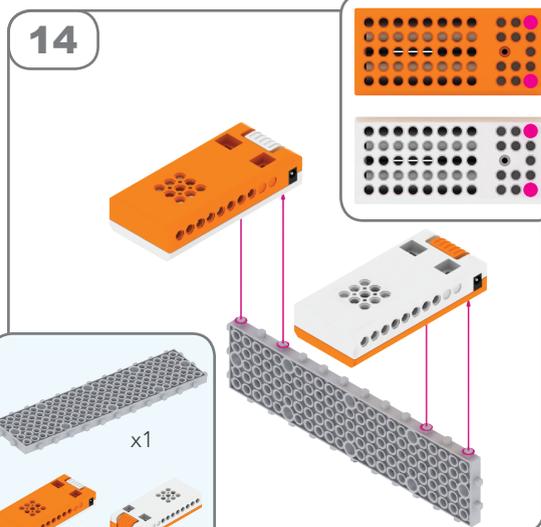
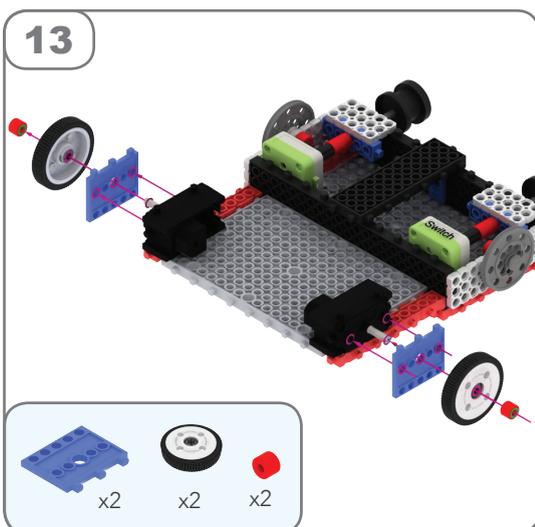
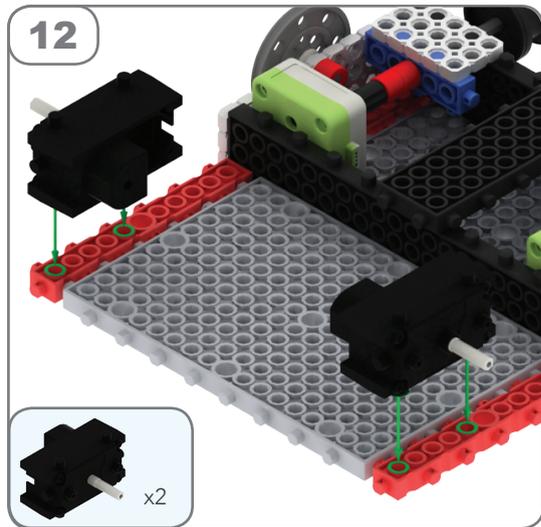
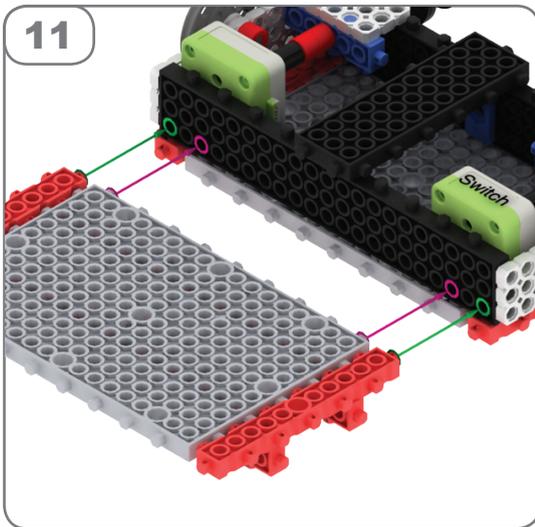
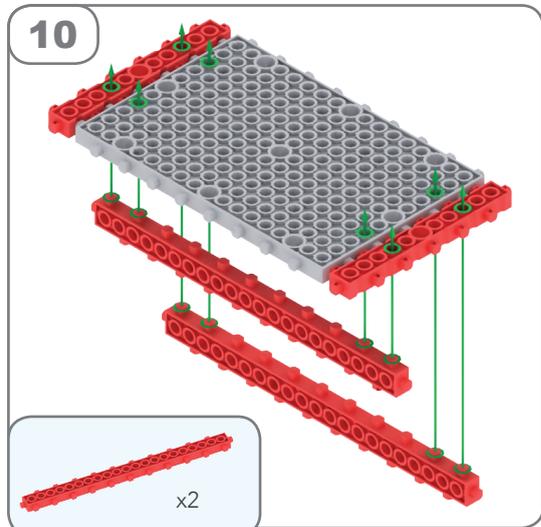
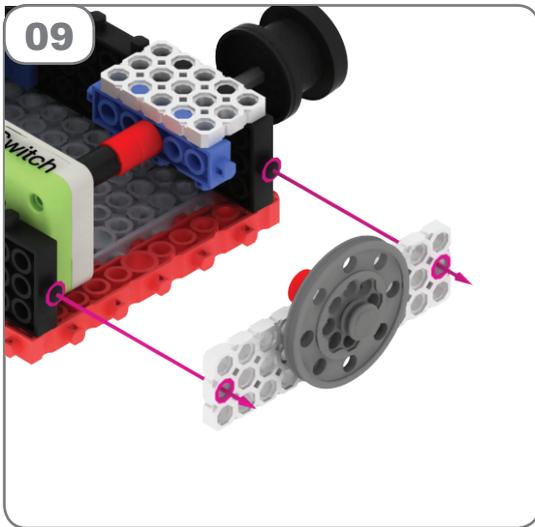


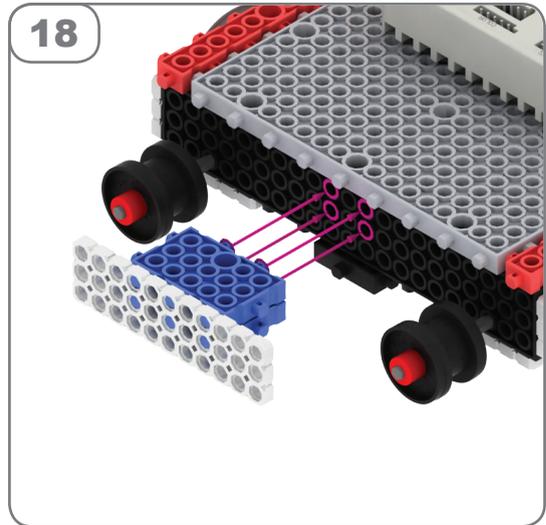
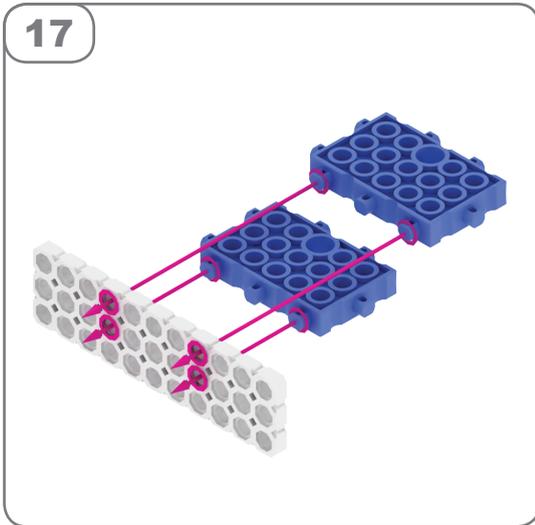
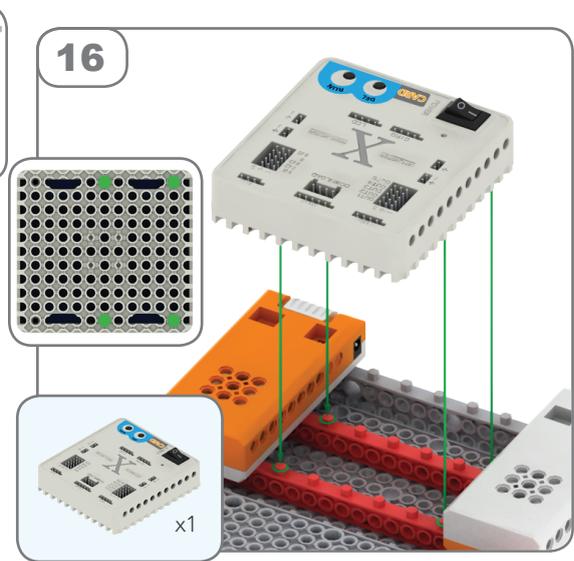
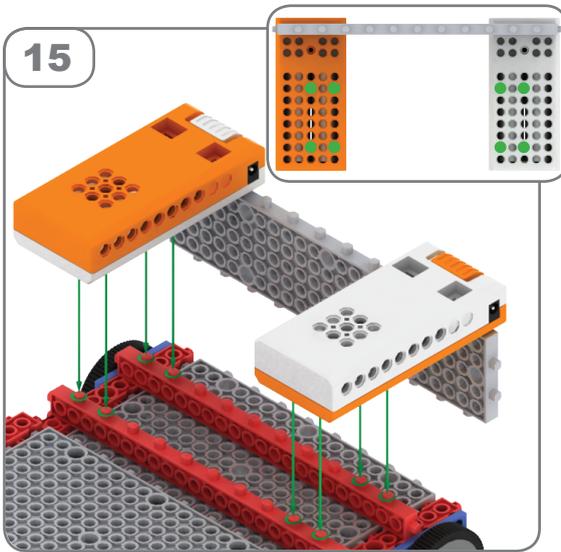
07



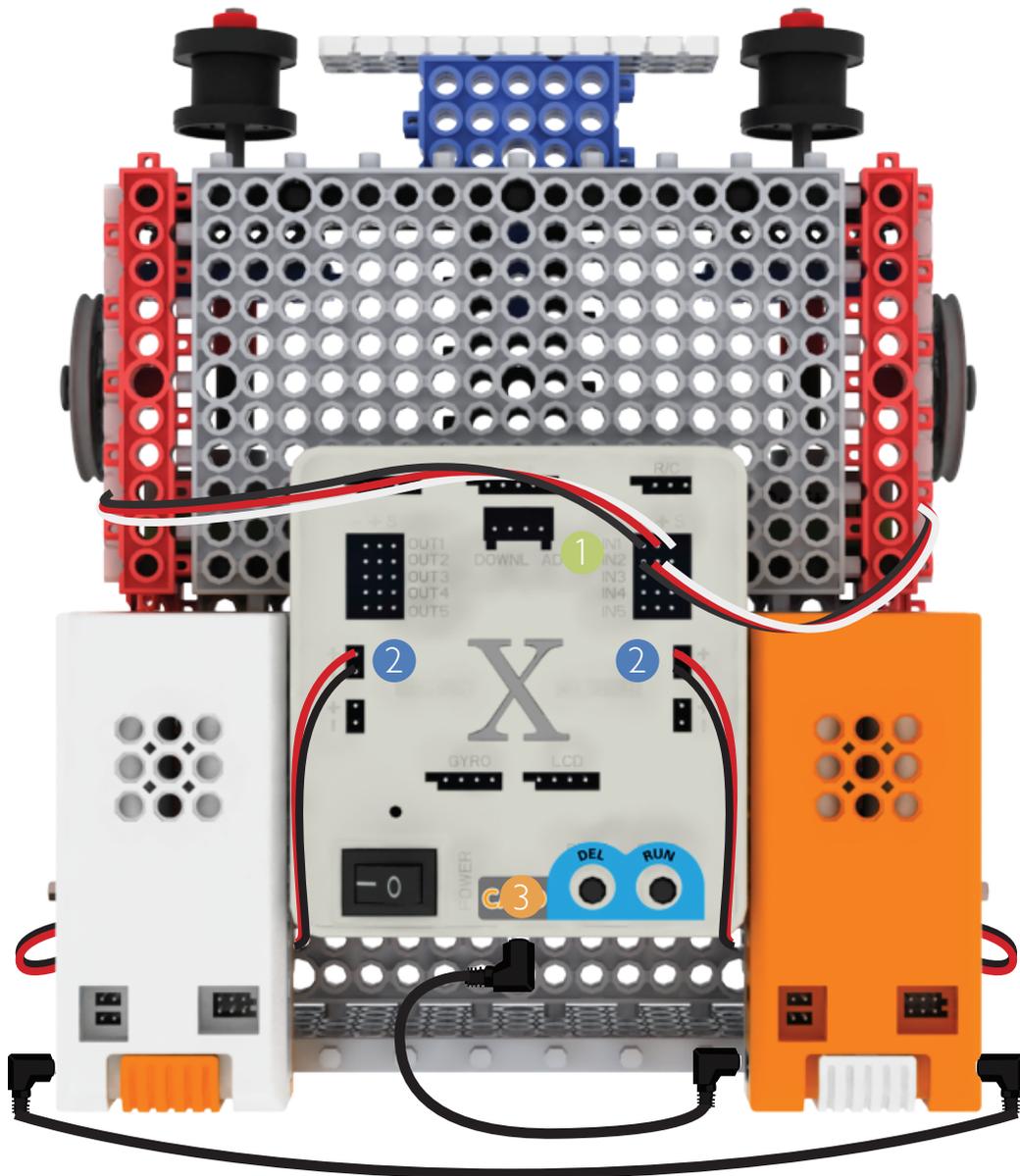
08







¿Cómo hacer la conexión?

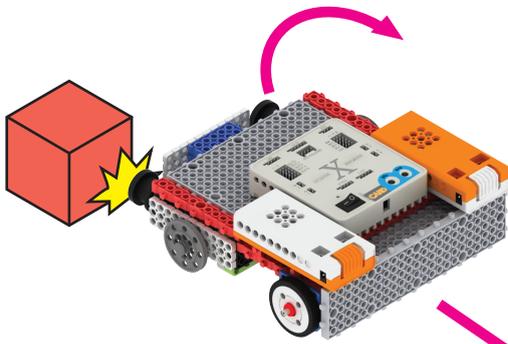


- 1 Conecta el sensor pulsador izquierdo en el puerto IN1 y el derecho en el puerto IN2, tal y como indica la imagen.
- 2 Conecta los dos motores con la placa base, tal y como se muestra arriba.
- 3 Conecta los dos portapilas con la placa base.

Los portapilas suministrarán energía cuando se conecten a la placa con el cable de conexión negro, independientemente de la posición de sus interruptores.

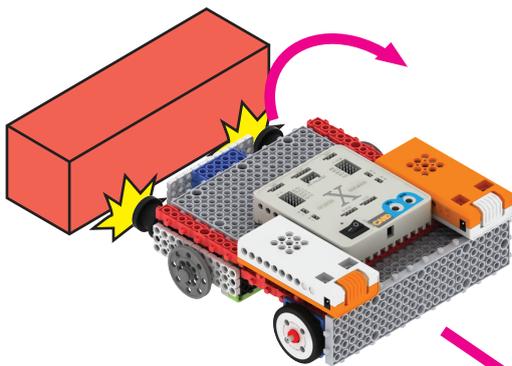
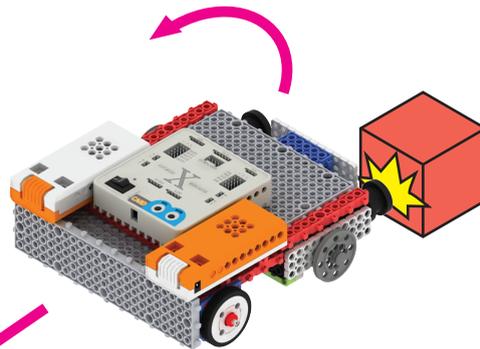
Practica

Enciende la placa, luego pulsa el botón RUN y después el DEL. La X parpadeará en rojo, entonces pulsa RUN para activar el modo 2 preprogramado. El robot se moverá hacia delante.



Cuando el sensor izquierdo encuentra un obstáculo, el coche de choque retrocede y luego gira a la derecha.

Cuando el sensor derecho encuentra un obstáculo, el coche de choque retrocede y luego gira a la izquierda.



Cuando ambos sensores encuentran un obstáculo, el coche de choque retrocede y luego gira a la derecha.