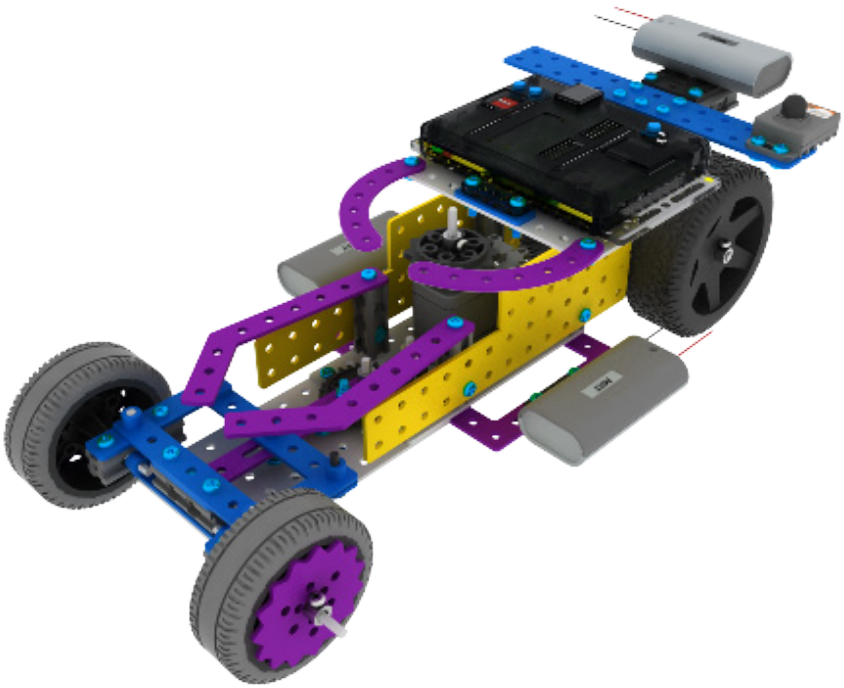
my robot time

MRT

Training course Of Professional

STEP I



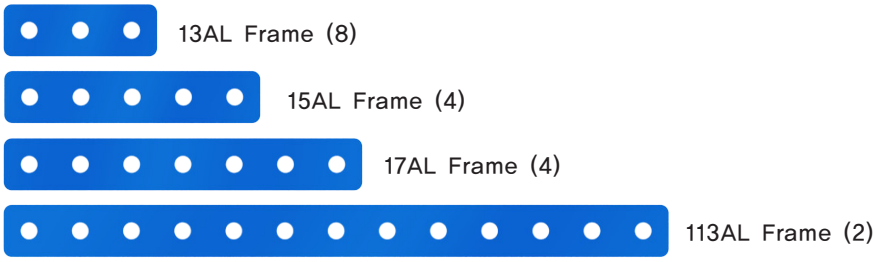
Training course Of Professional I

CONTENTS

Packing list

AL frame and steel bracket

※ AL : Aluminum


13AL Frame (8)

15AL Frame (4)

17AL Frame (4)

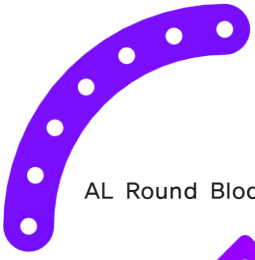
113AL Frame (2)


AL Sprocket (2)


27AL Frame (2)


17AL Frame (2)


213AL Frame (2)


AL Round Block (2)

39AL Frame (2)


AL Frame135 (2)

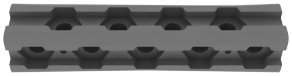
59AL Frame (2)

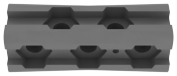

AL Frame90 (4)

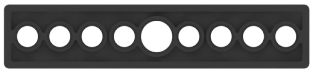
D90 S-Bracket (4)

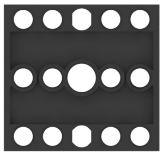

D135 S-Bracket (4)

Pillar and Motor Mount


4-5 Pillar block (6)


2-3 Pillar Block (8)


9 Hole Motor Mount (4)


Motor Mount (4)

Steel Shaft and Bush

Steel shaft 31mm (4)

Steel shaft 44mm (4)

Steel shaft 70mm (2)

Steel shaft 95mm (2)

Steel shaft 120mm (2)

ABS Connecting shaft (4)

B–Bush (20)

Coupling (4)

Half–Bush (10)

Bolt and nut

Bolt 8mm (40)

Bolt 16mm (40)

Bolt 20mm (20)

Nut (100)

Washer (40)

Gear and Wheel

Big Wheel2 (2)

Big Wheel1 (2)

S–Gear (2)

Sprocket (4)

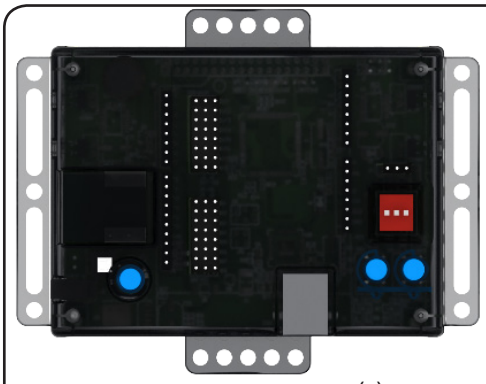
L–Gear (2)

M–Gear (2)

Guide Wheel (2)

Caterpillar (80)

Mainboard and Electronic Parts



MRT5–1 Main board (1)

DC MOTOR (2)

IR Sensor (3)

RC Receiver (1)

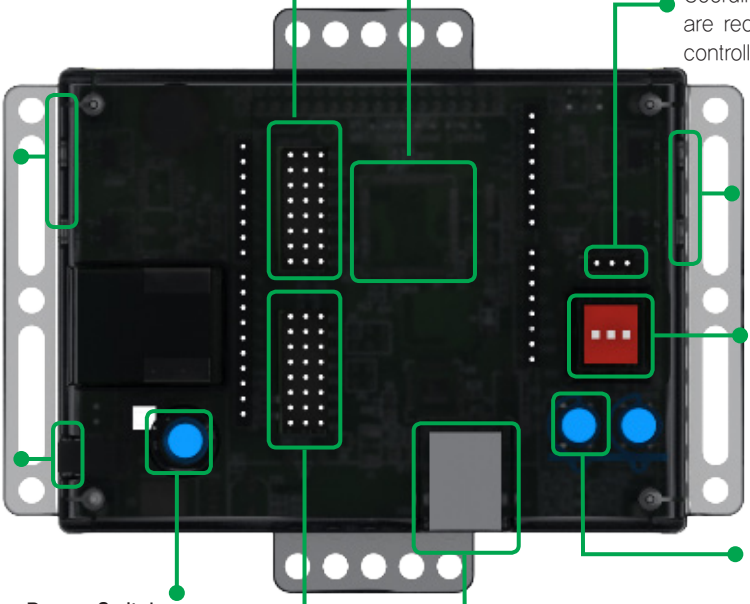
Touch Sensor

Remote Controller

9V Battery Case (1)

Electric parts

Mainboard assemble



N–PUT Connector
Receives input value by connecting with switches and various of sensors (IR Sensor, Touch, CDS, MIC...)

MCU
Saving and running program and acts in the role of the brain.

RC Receiver connector
Coordinates the signals that are received from the remote controller.

DC Motor connector
Coordinates the functions of the left motor

DC Motor connector
Coordinates the signals from the right motor.

Modify Remote Controller ID Switch.

Power Connector
Connects to the battery case .

Restart Button
Restart the mainboard.

Power Switch
Power on/off switch.

OUT–PUT connector
This result is processed and written by program and send to sensors (LED, Buzzer DC motor and so on).

Download connector
Download the program from PC to MCU.

Various of Sensors and Function

Send light
An infrared signal is sent to the object.
If there is a reflection, the information is sent to the "receive" light part.

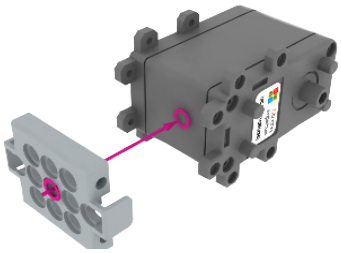
Receive light
This receives the signal from the above part and converts that signal into the input signal.

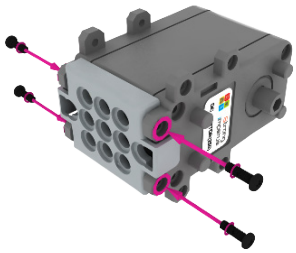
IR RC Receiver
Receive the IR signal from remote controller and convert into input signal

Touch Sensor
Set the output signal as ON/OFF function

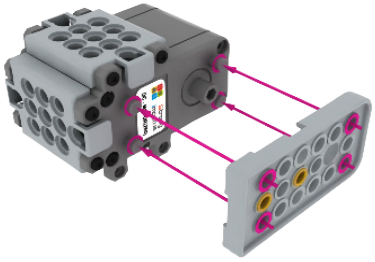
The usage of DC Motor

The assemble of DC motor

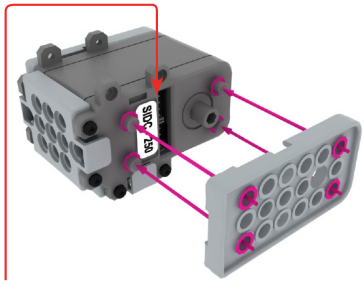




Assemble DC motor with motor mount block

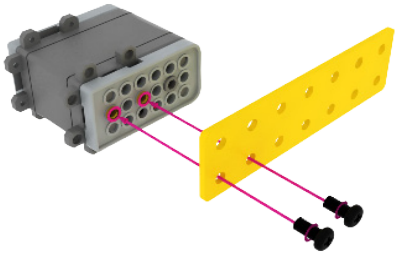


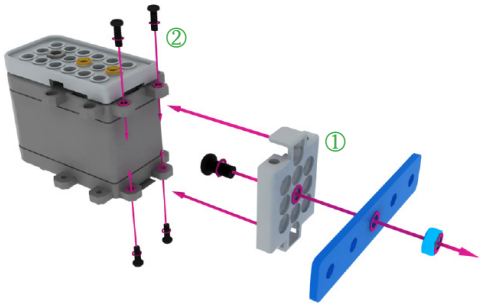
1.Use the insert module to fix frame.



2.Insert the line first and then assemble the DC motor.

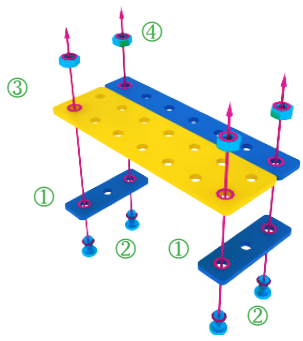
Assemble frame and motor

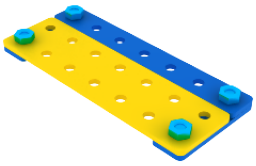




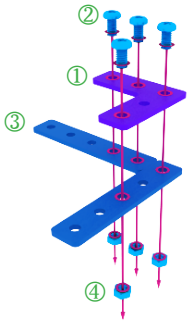
Learn how to assemble each part and its function

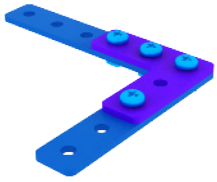
Assemble frame





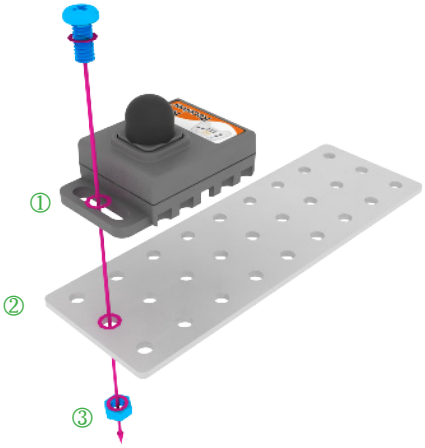
① Frame ➡ ② Bolt ➡ ③ Frame ➡ ④ Nut

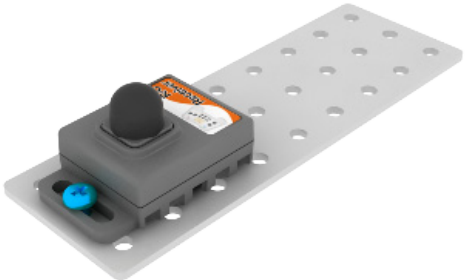




① Frame ➡ ② Bolt ➡ ③ Frame ➡ ④ Nut

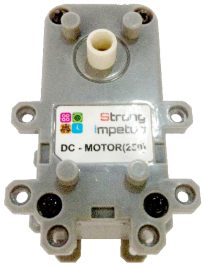
Assemble sensor and frame

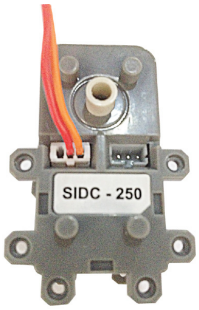


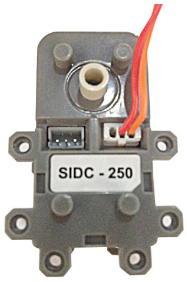


① Frame ➡ ② Bolt ➡ ③ Sensor

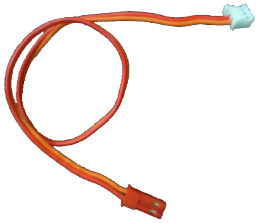
Assemble motor line





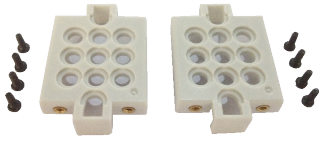


Connect to the side which is easier to connect.



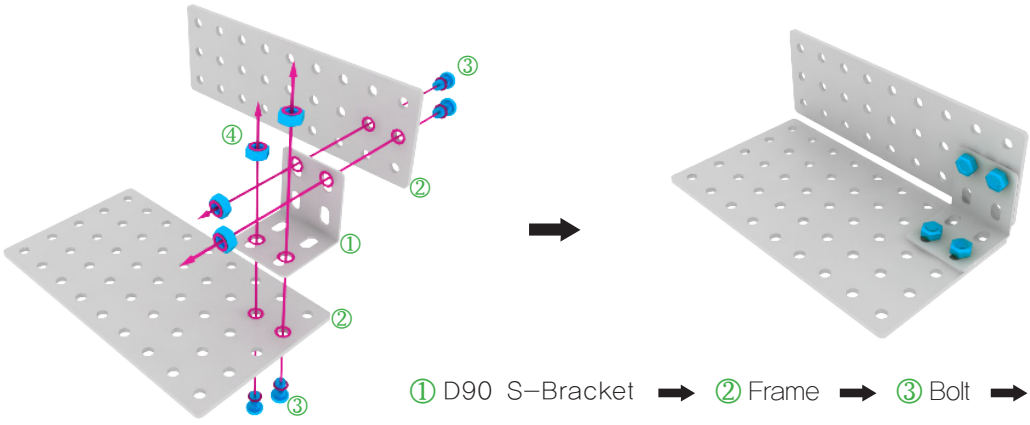
Motor line

Motor Mount



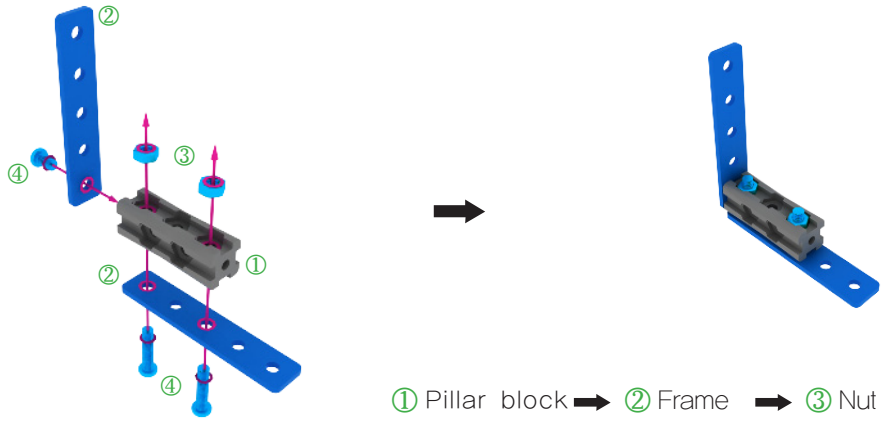
Motor block

Assemble frame and D90 S- Bracket

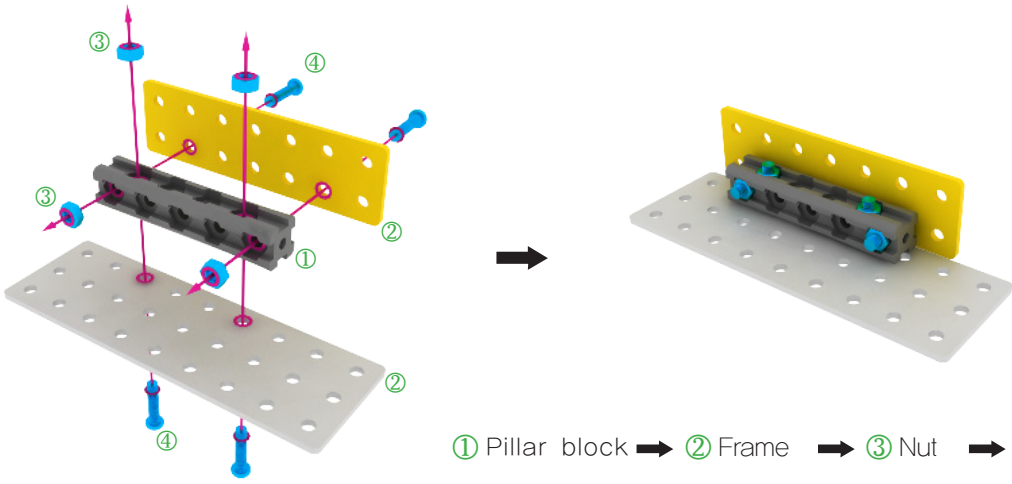


① D90 S-Bracket ➡ ② Frame ➡ ③ Bolt ➡ ④ Nut

Assemble frame and pillar block



① Pillar block ➡ ② Frame ➡ ③ Nut ➡ ④ Bolt



① Pillar block ➡ ② Frame ➡ ③ Nut ➡ ④ Bolt

※ Fix the nut onto the pillar block first when combined with each frame.

Steel Shaft Scale drawing

Steel shaft 31mm

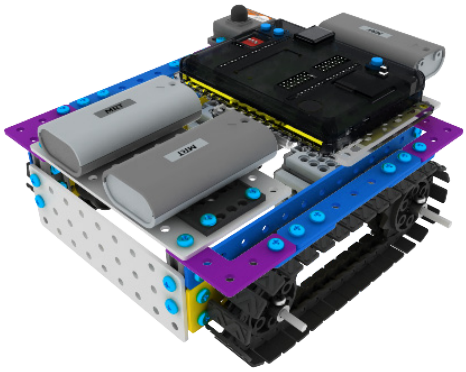
Steel shaft 44mm

Steel shaft 70mm

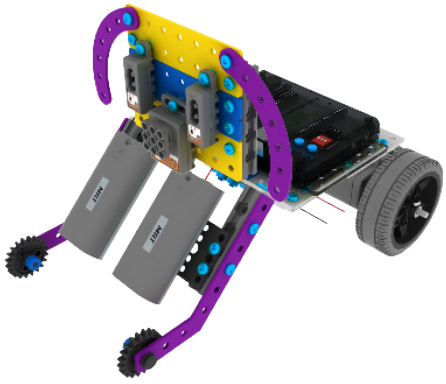
Steel shaft 95mm

Steel shaft 120mm

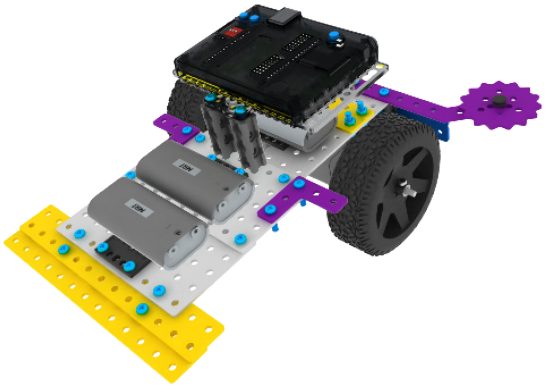
Learn how to assemble these robots !



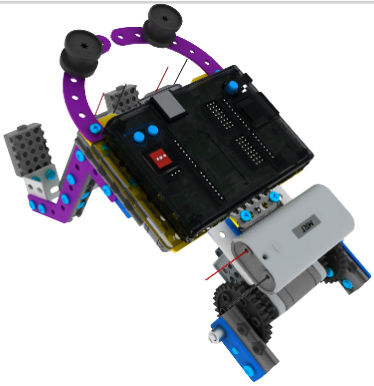
1. Basic Tank



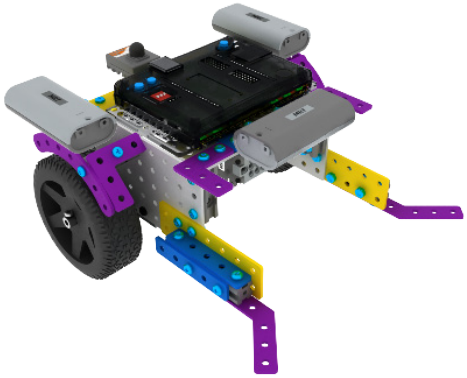
2. Dog Stalker



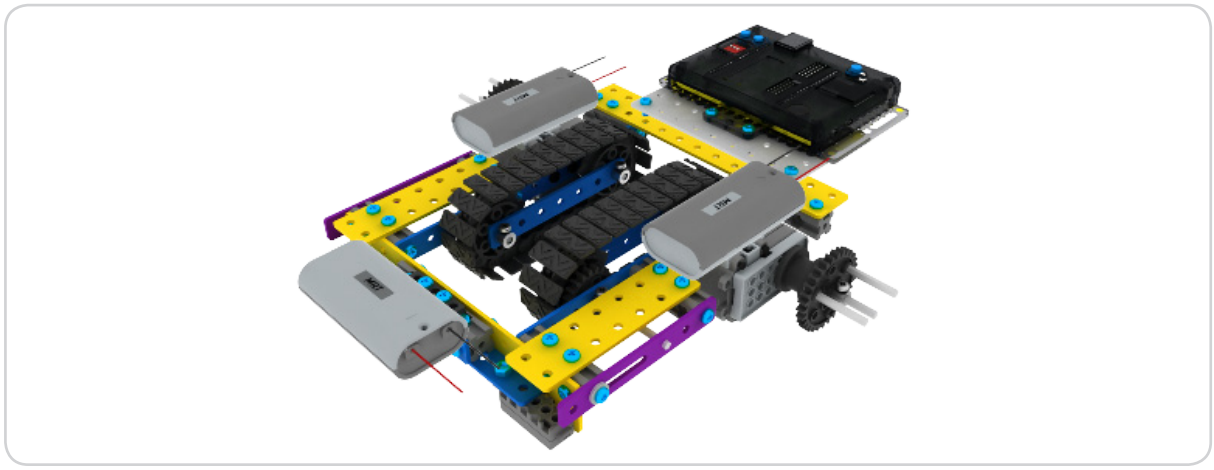
3. Battle Robot



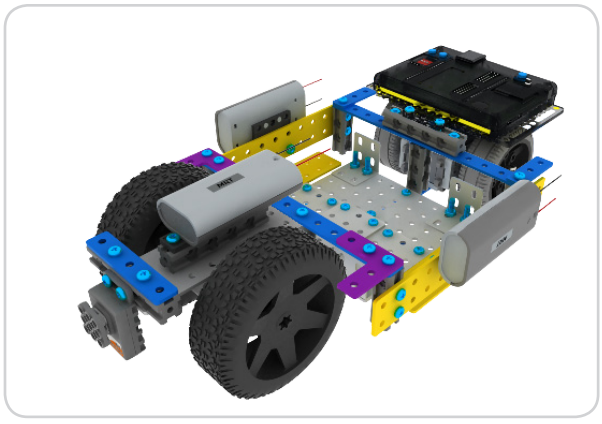
4. Frog–Bot



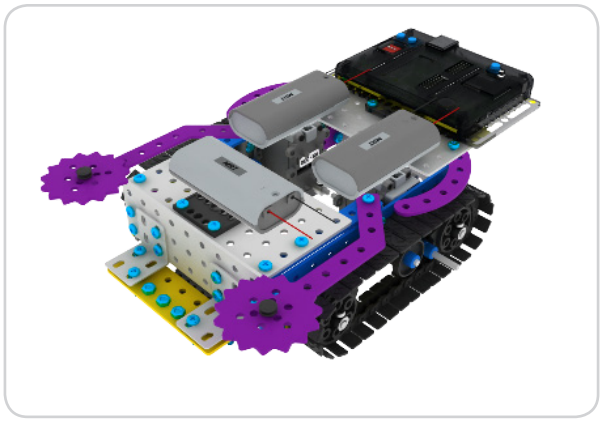
5. Soccer Robot



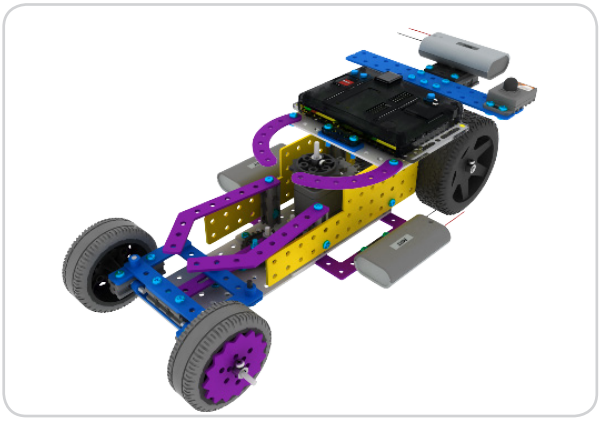
6.Drop Checker



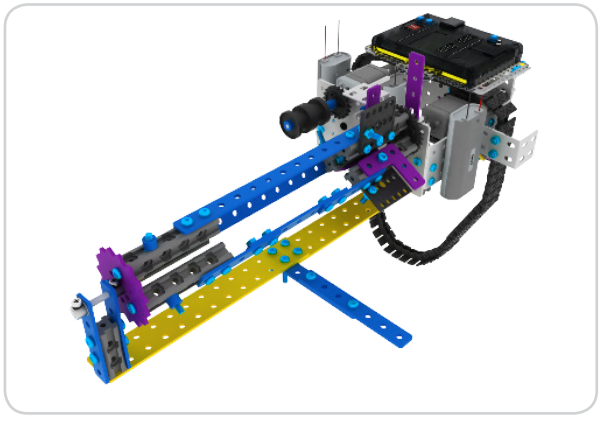
7. Shuttle Carrier



9. Tracing Tank



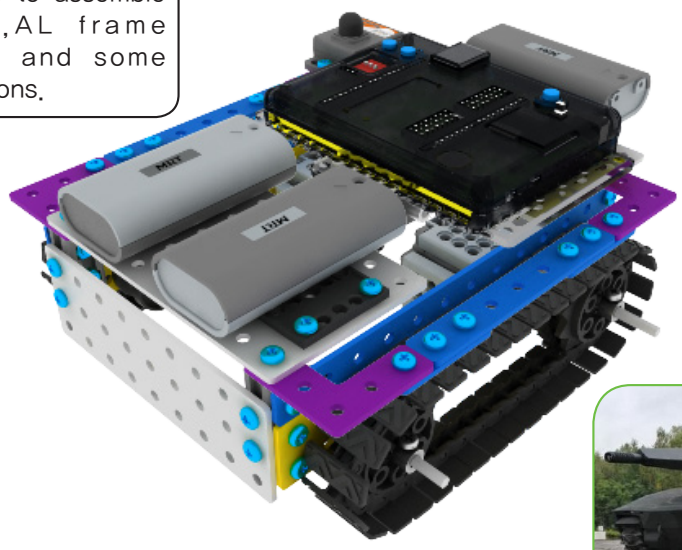
9.Classic Car



10. Machine Gun

BASIC TANK

To learn how to assemble DC motor,AL frame ,Caterpillar and some basic operations.

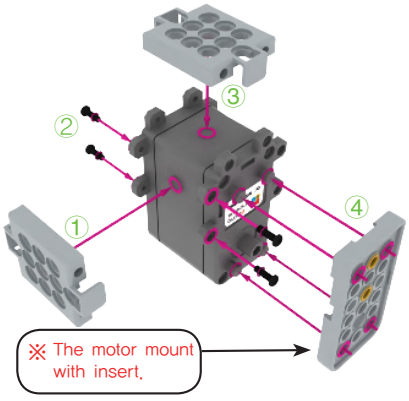


Name	Picture	Quantity
Steel Lshaft 95mm		2
Steel shaft 70mm		2
13AL Frame		4
15AL Frame		1
17AL Frame		2
113AL Frame		2
213AL Frame		2
39AL Frame		2
59AL Frame		2
Motor Mount		3
2-3Pillar Block		4

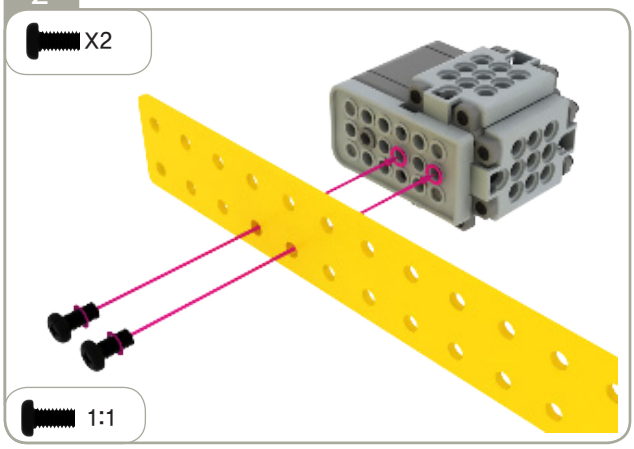
Name	Picture	Quantity
9V Battery Case		1
MRT5-1 Main board		1
DC MOTOR		2
Remote Controller		1
AL Frame90		4

Name	Picture	Quantity
Bolt		4
Bolt 8mm		15
Bolt 16mm		22
Nut		32
Half-Bush		4
Guide Wheel		2
M-Gear		2
L-Gear		4
Sprocket		4
Sleeve pipe		8
RC Receiver		1
Caterpillar		66

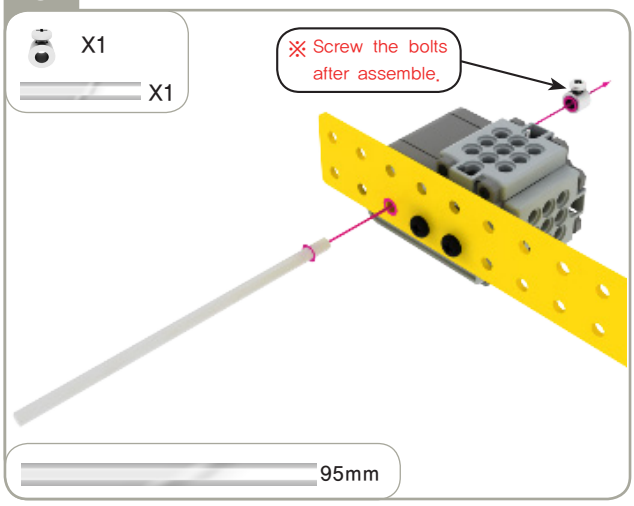
1


③
②
①
④
※ The motor mount with insert.

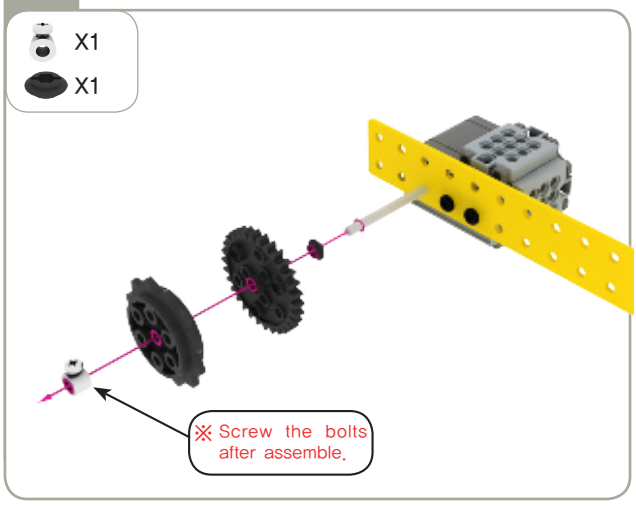
2


X2
1:1

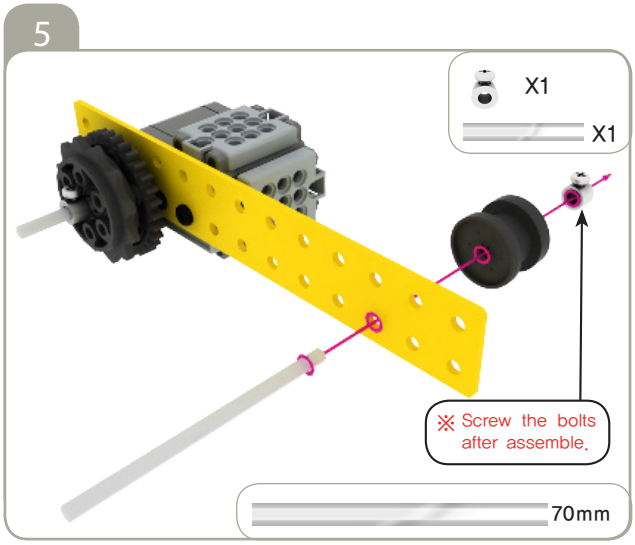
3


X1
X1
※ Screw the bolts after assemble.
95mm

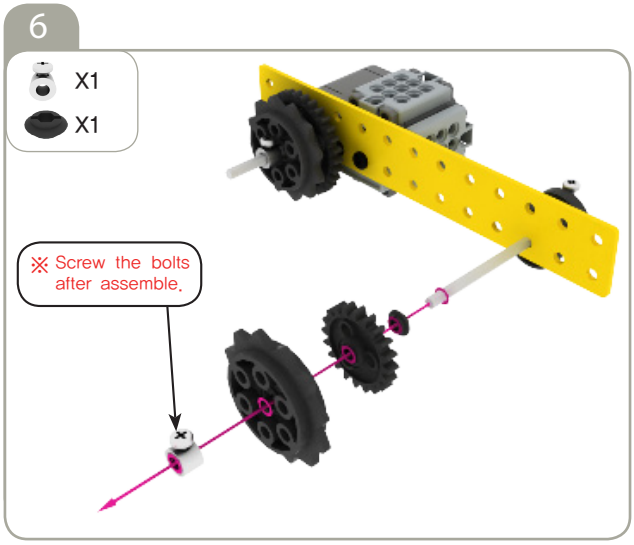
4


X1
X1
※ Screw the bolts after assemble.

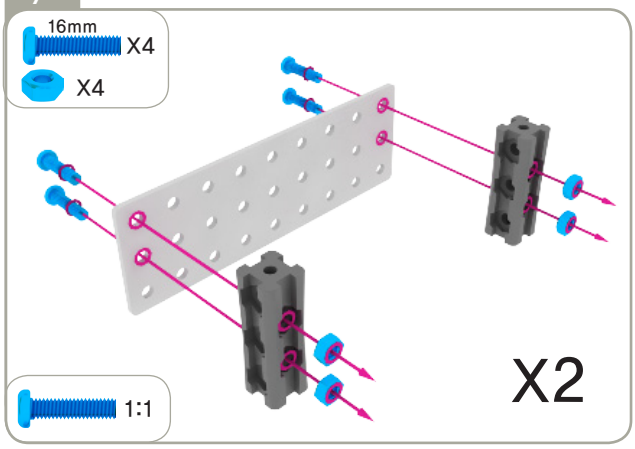
5


X1
X1
※ Screw the bolts after assemble.
70mm

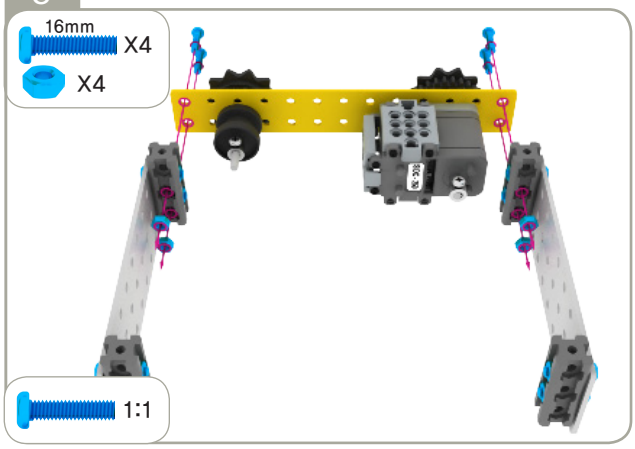
6


X1
X1
※ Screw the bolts after assemble.

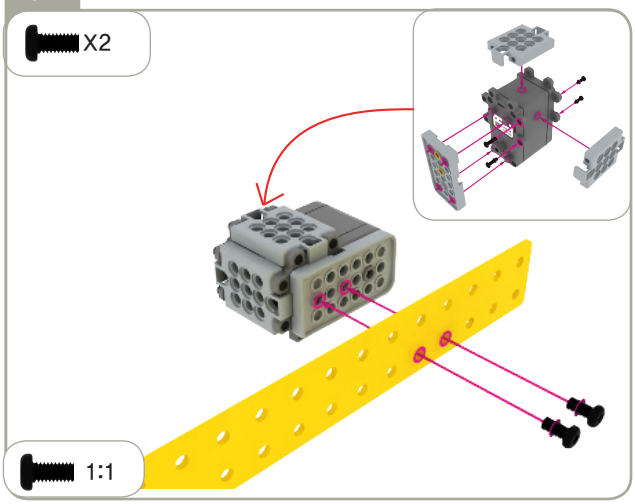
7


16mm
X4
X4
X2
1:1

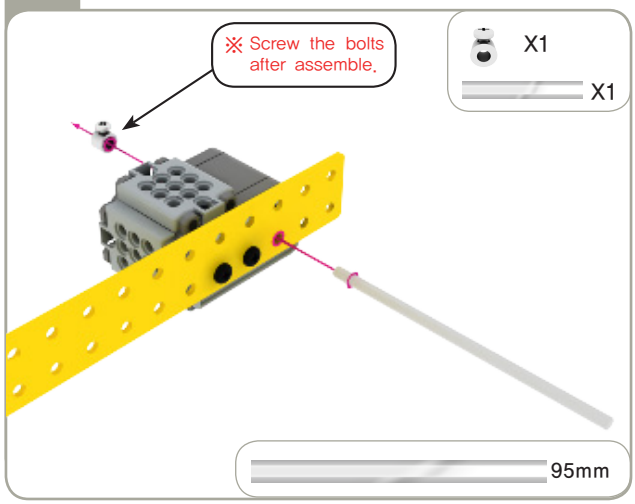
8


16mm
X4
X4
1:1

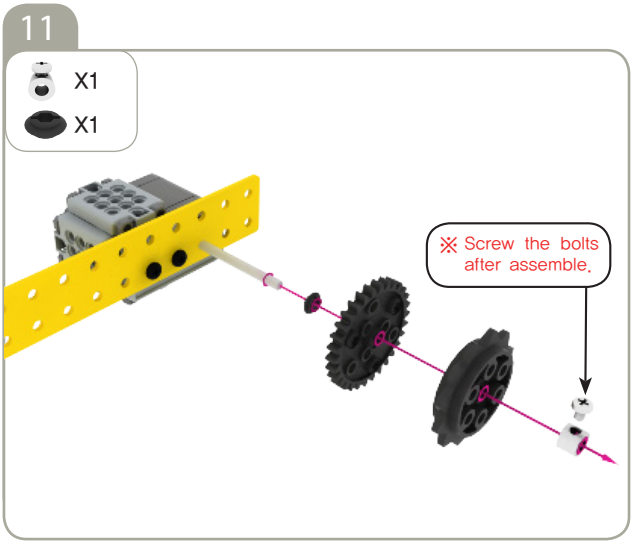
9


X2
1:1

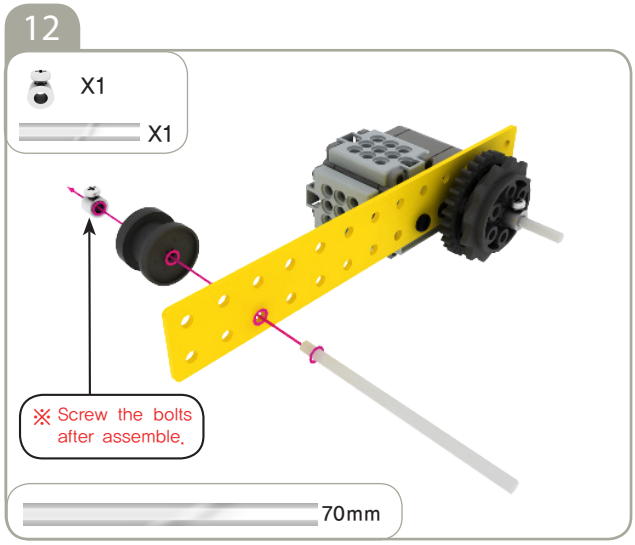
10


※ Screw the bolts after assemble.
X1
X1
95mm

11

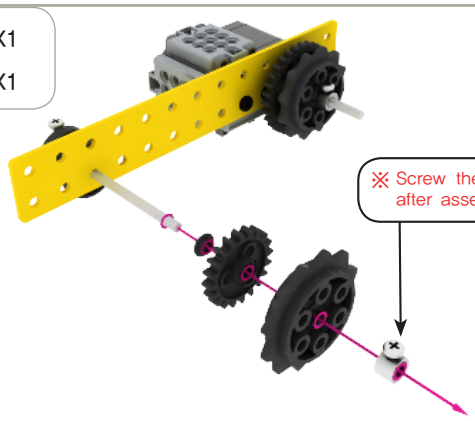

X1
X1
※ Screw the bolts after assemble.

12


X1
X1
※ Screw the bolts after assemble.
70mm

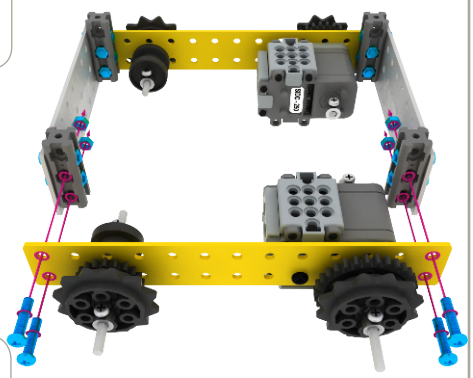
13

X1
X1



14

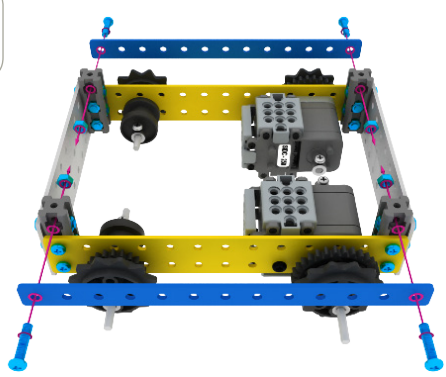
16mm X4
X4



1:1

15

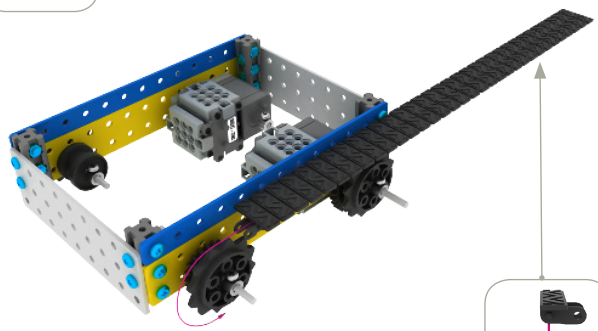
16mm X4
X4



1:1

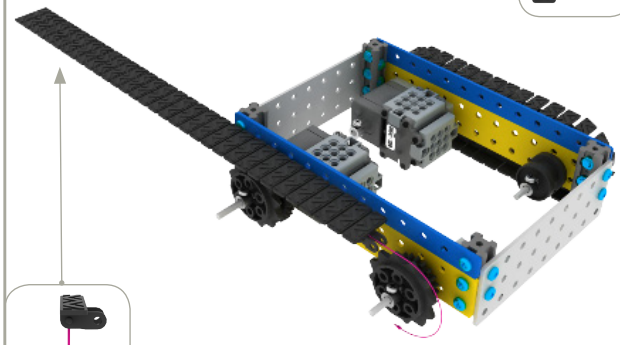
16

X33



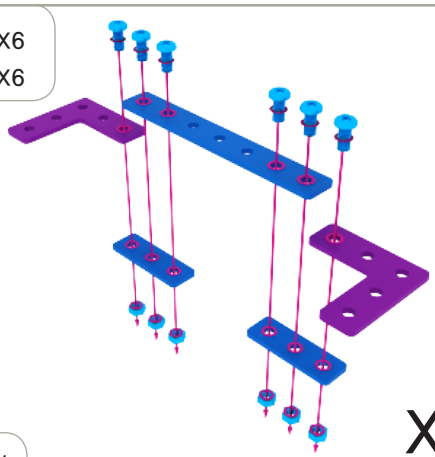
17

X33



18

8mm X6
X6



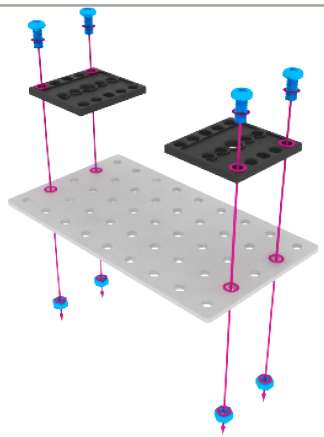
X2

1:1

19

8mm X4

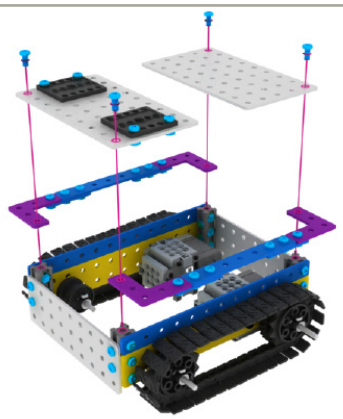
X4



1:1

20

8mm X4

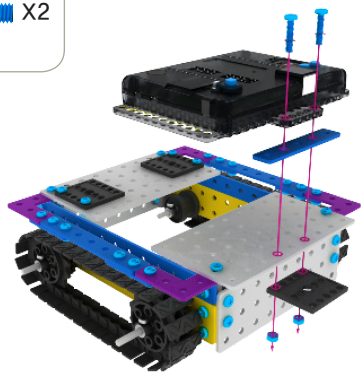


1:1

21

16mm X2

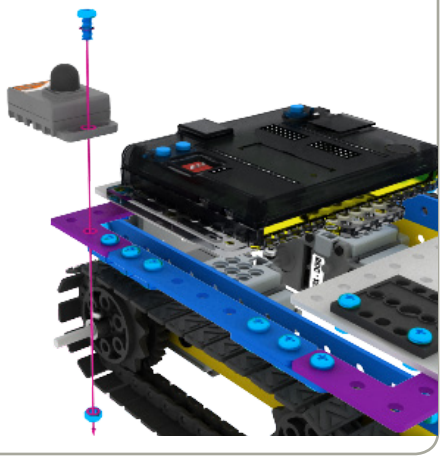
X2



1:1

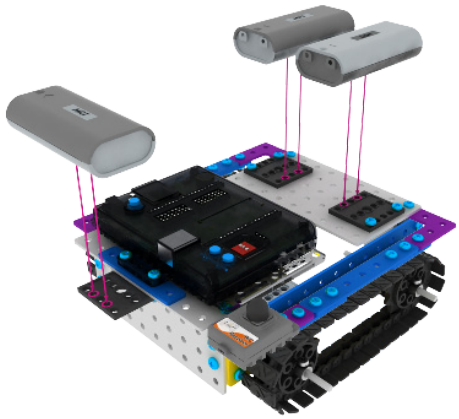
22

8mm X1

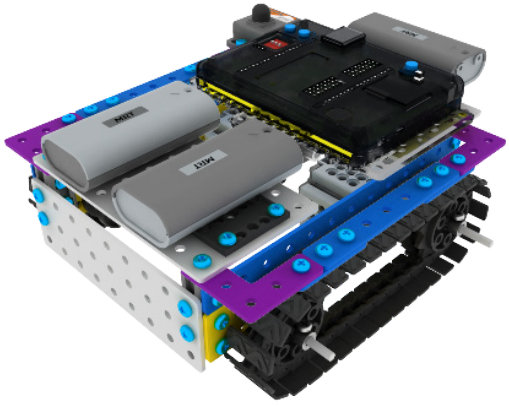


1:1

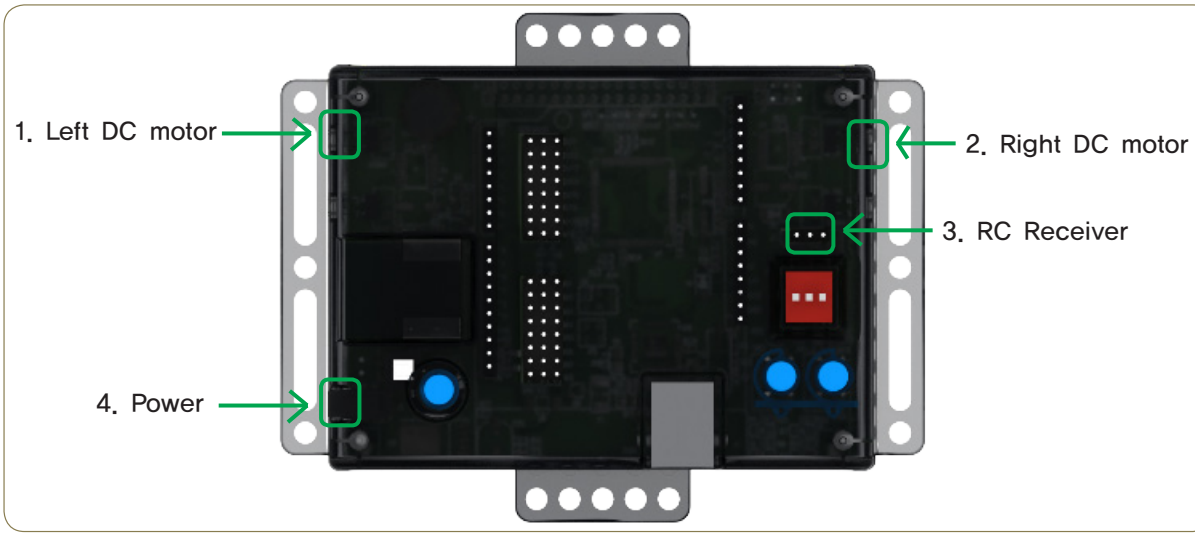
23



Complete



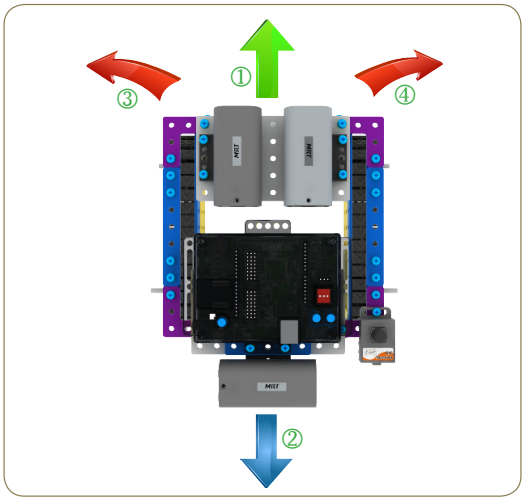
Connecting the mainboard



Please connect in this order:

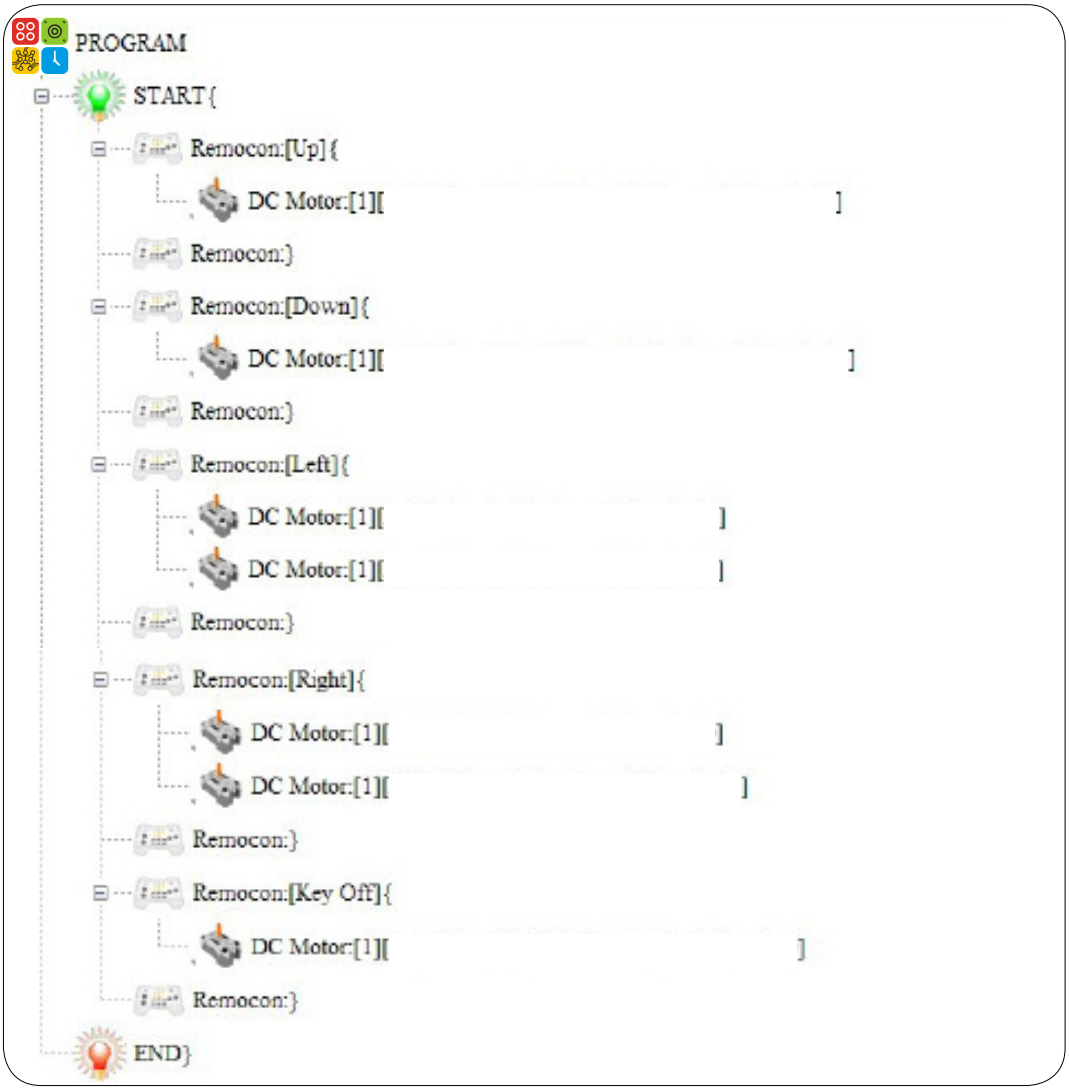
1. Connect left DC motor to L–MOTOR connector.
2. Connect right DC motor to R–MOTOR connector.
3. Connect RC Receiver to R/C connector.
4. Connect battery case to Power connector.

Motion Pattern



Learn to compile program in advance

※ Try to write down the program before we compile on software.



1. Press the directional key (up/down) of remote controller, the robot will move forward and backward.
2. Press the directional key (left / right) of remote controller, the robot will move left and right .
3. It's possible to compile the program as your idea, like press "up" and "left/right" together or press "down" and "left/right"together.

※ Program example : Refer to the back of book.

Program download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download to start".
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

DOG STALKER

Dog stalker visualize the puppy following people, when the IR sensors (eyes of puppy) recognize signal, it will go forward or turn left and right.
The puppy will walk backward when touch its nose.

Name	Picture	Quantity
Steel shaft 31mm		1
Steel shaft 70mm		2
13AL Frame		3
17AL Frame		2
27AL Frame		2
39AL Frame		2
59AL Frame		2
4–5 Pillar block		4
2–3 Pillar Block		1
Motor Mount		3

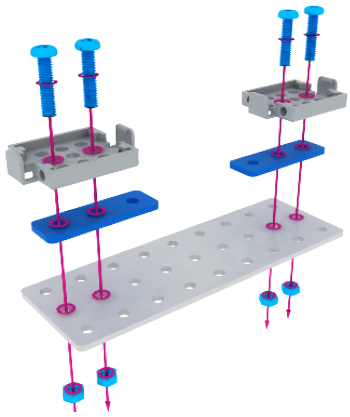
Name	Picture	Quantity
9V Battery Case		1
MRT5–1 Main board		1
DC MOTOR		2
AL Round Block		2
AL Frame135		2

Name	Picture	Quantity
Bolt 8mm		27
Bolt 16mm		22
Nut		46
ABS Connecting shaft		2
B–Bush		5
M–Gear		2
Sleeve pipe		4
Big Wheel2		2
IR Sensor		2
Touch Sensor		1
D135 S–Bracket		4

1

16mm X4

X4

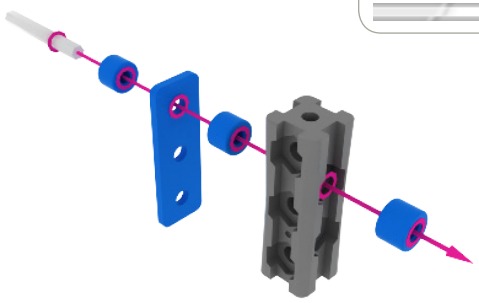


1:1

2

X3

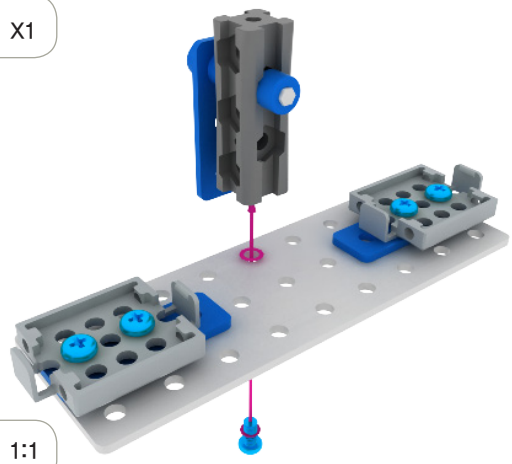
X1



31mm

3

8mm X1



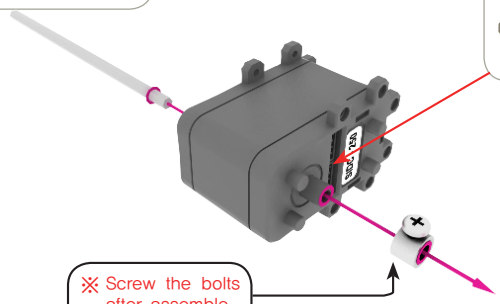
1:1

4

X1

X1

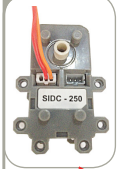
Connect the line of DC motor first.



※ Screw the bolts after assemble.

95mm

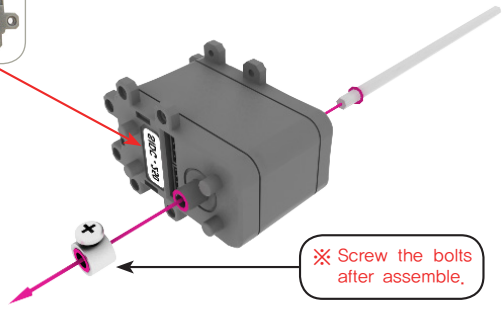
5



Connect the line of DC motor first.

X1

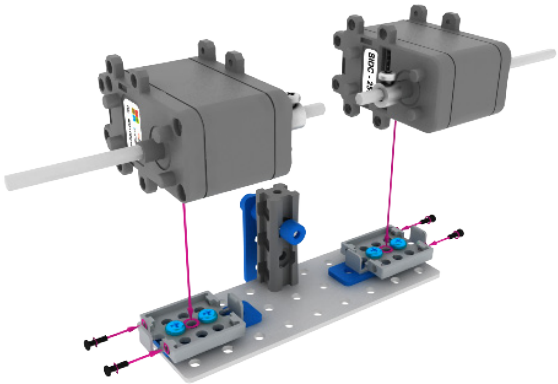
X1



※ Screw the bolts after assemble.

95mm

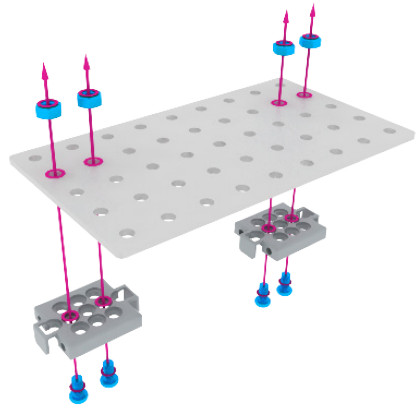
6



7

8mm X4

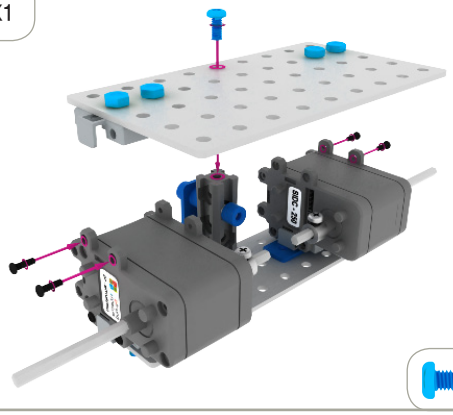
X4



1:1

8

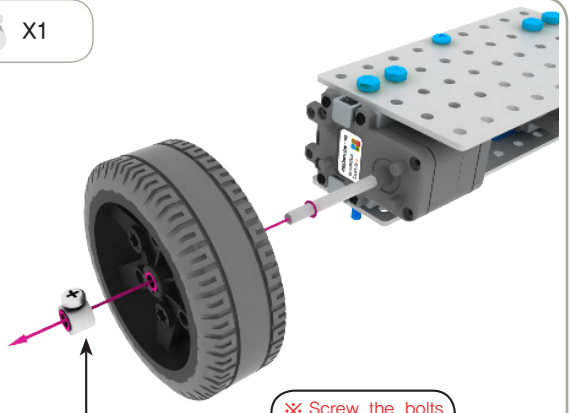
8mm X1



1:1

9

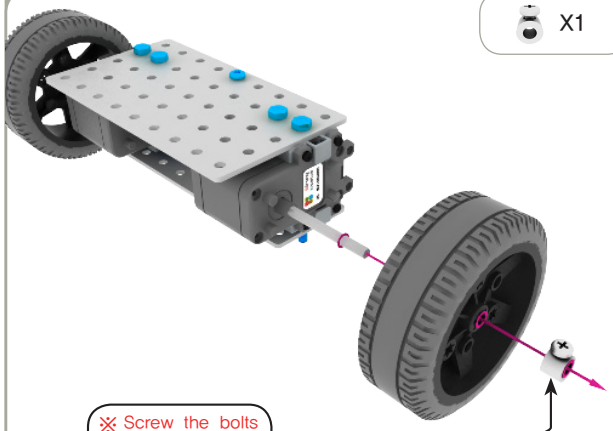
X1



※ Screw the bolts after assemble.

10

X1

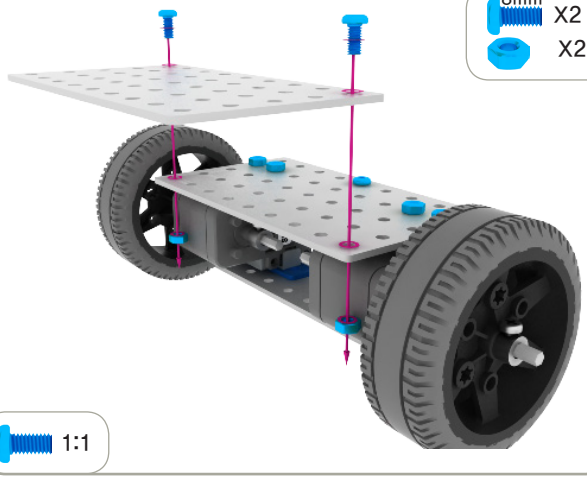


※ Screw the bolts after assemble.

11

8mm X2

X2

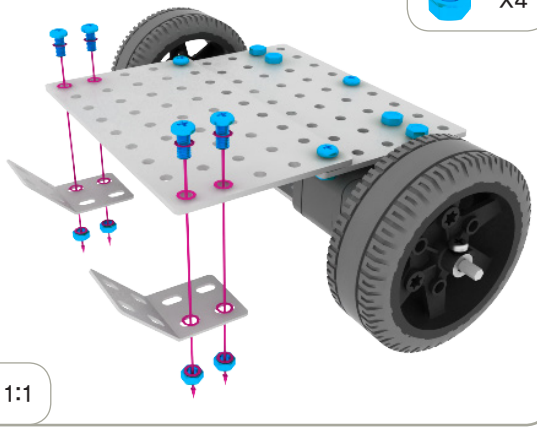


1:1

12

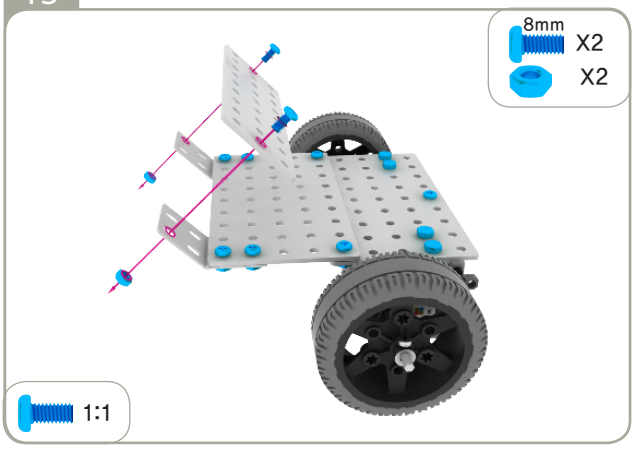
8mm X4

X4



1:1

13



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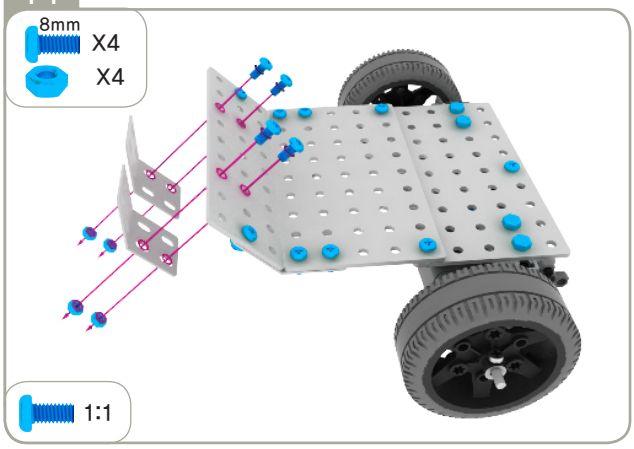

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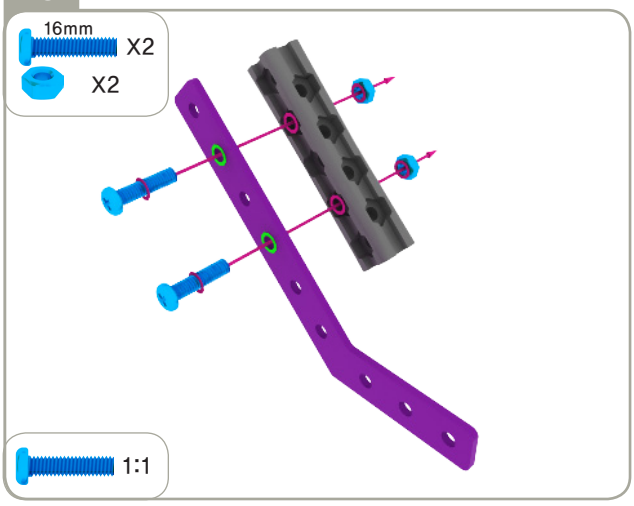

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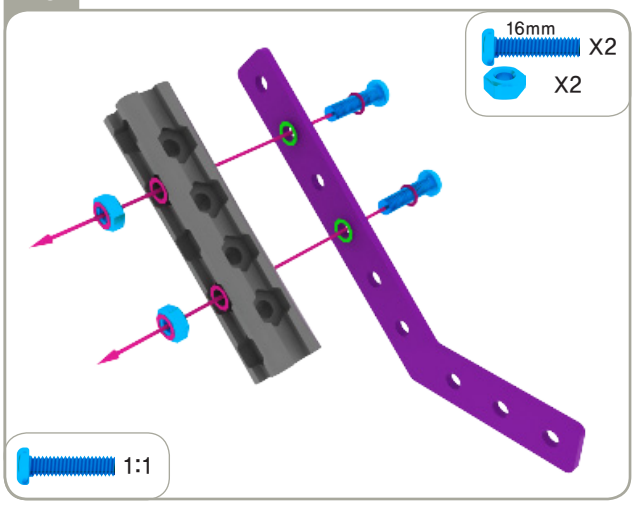

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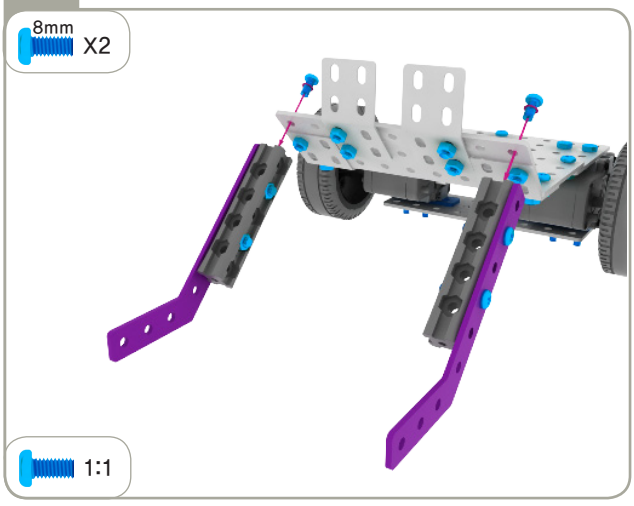

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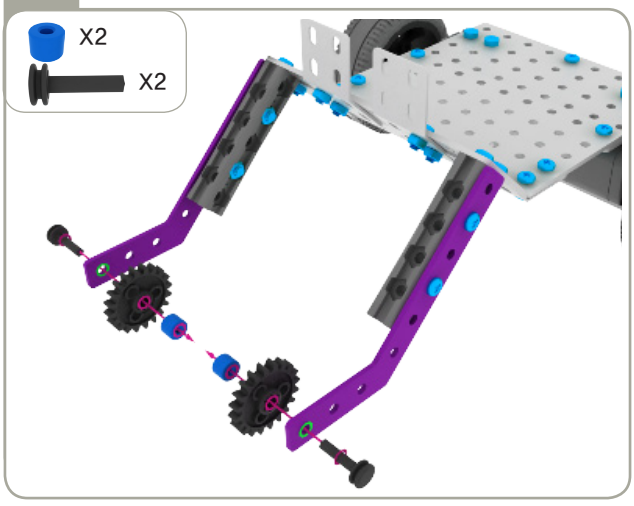

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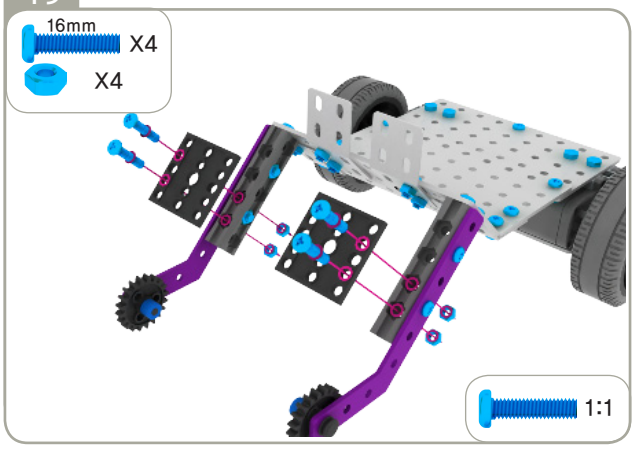

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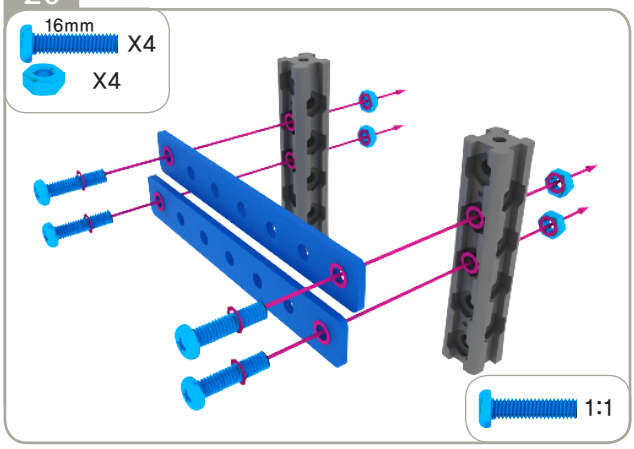

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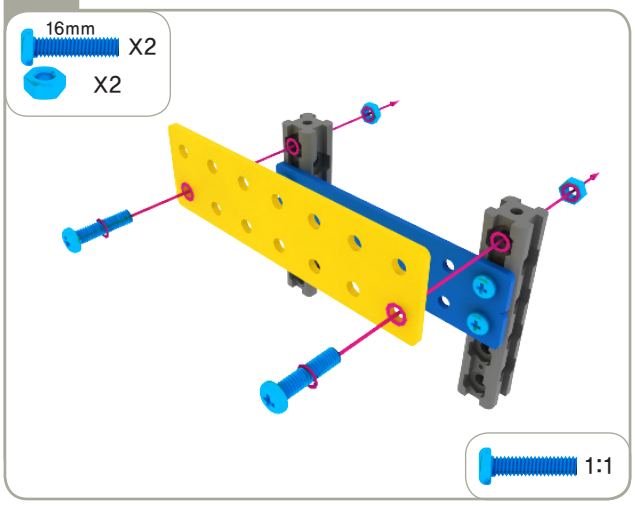

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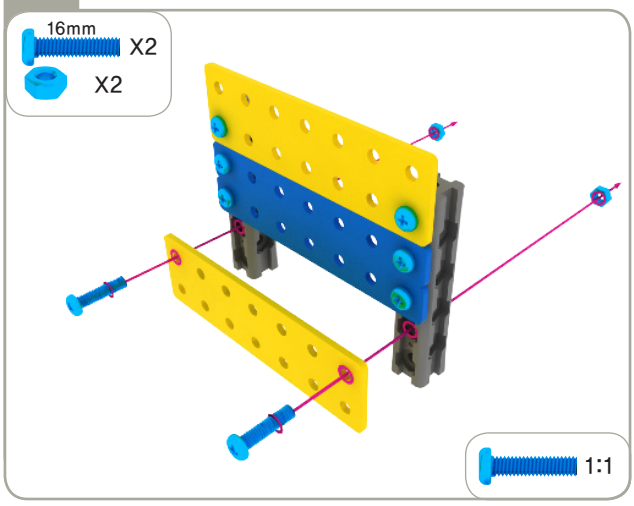

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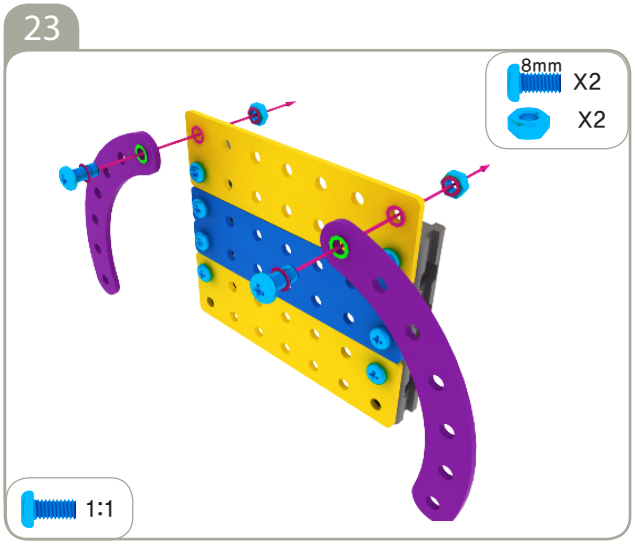

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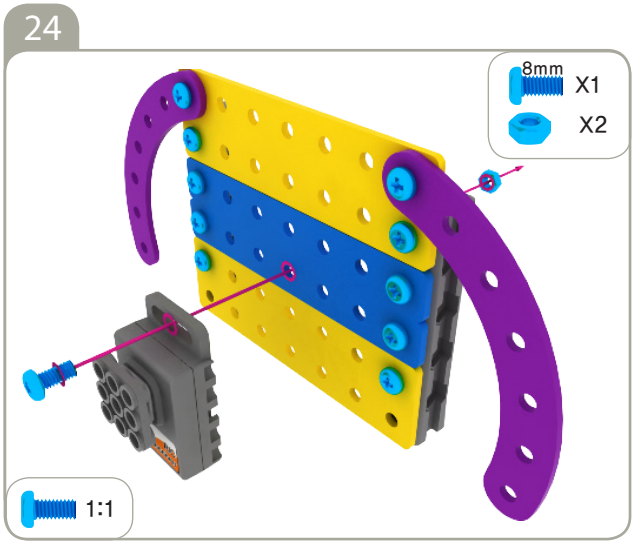
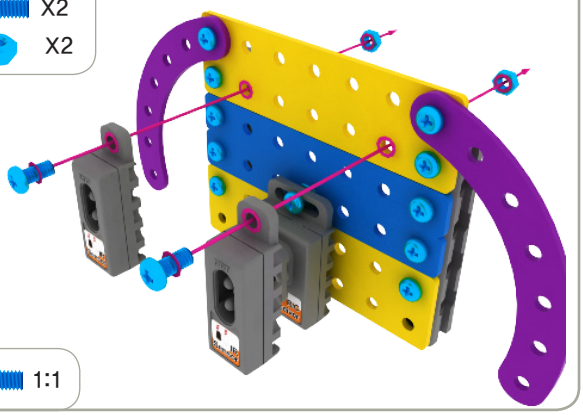


25

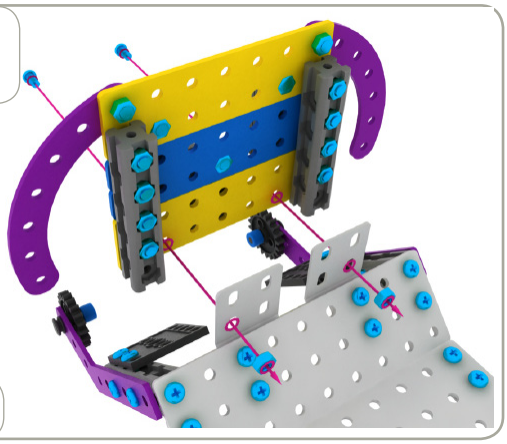
8mm X2
X2



1:1

26

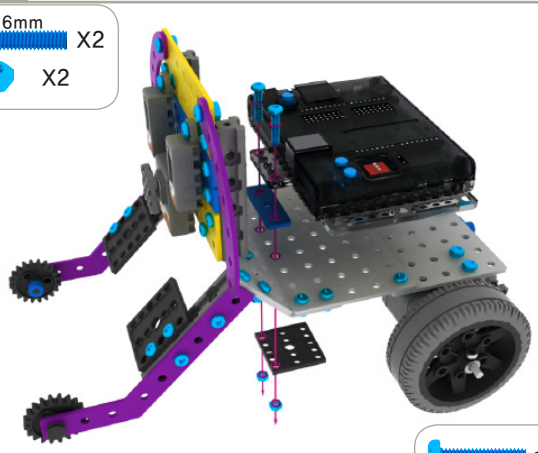
8mm X2
X2



1:1

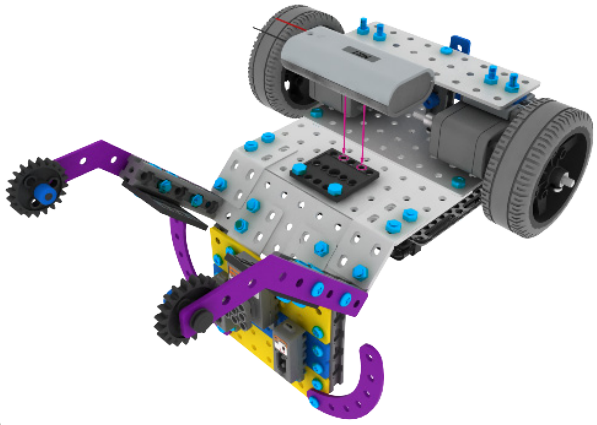
27

16mm X2
X2



1:1

28



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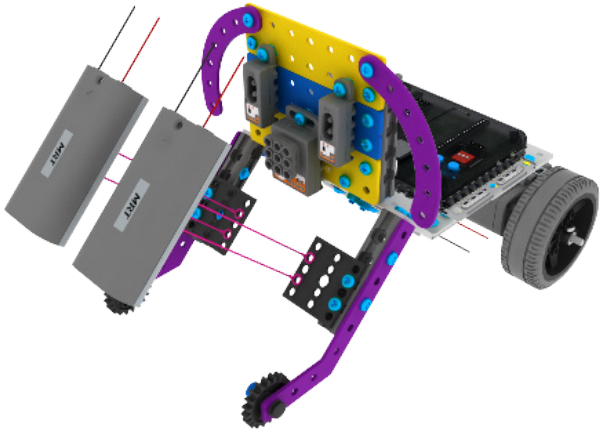
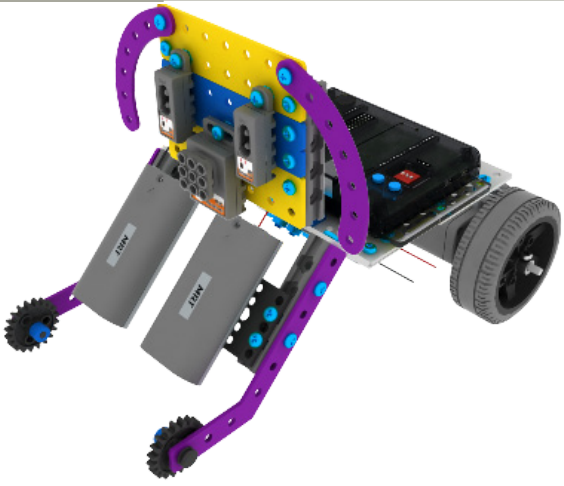
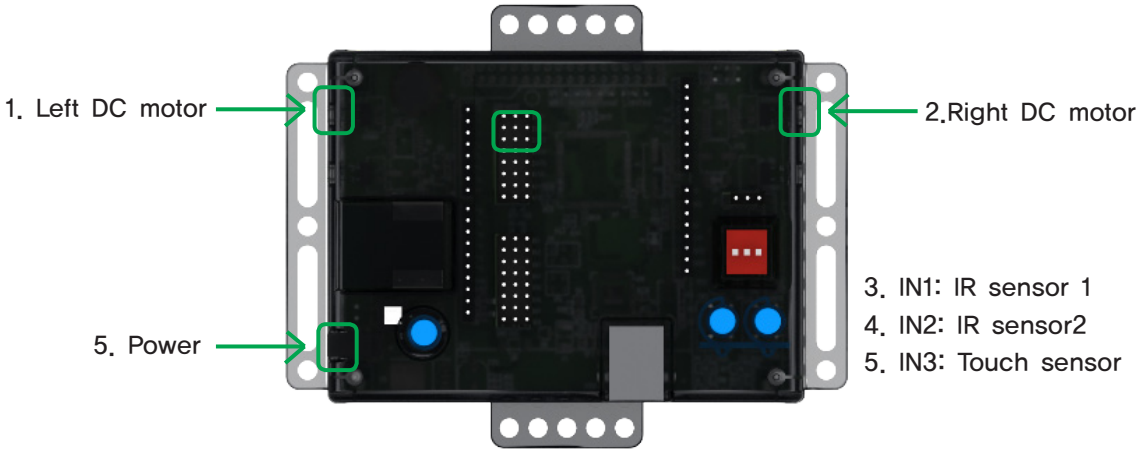


Complete



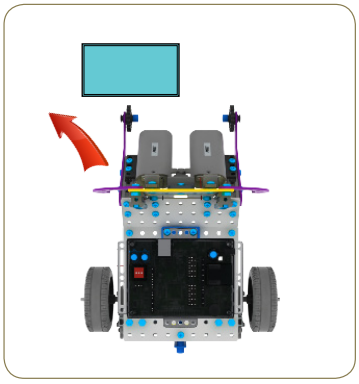
Connecting the mainboard



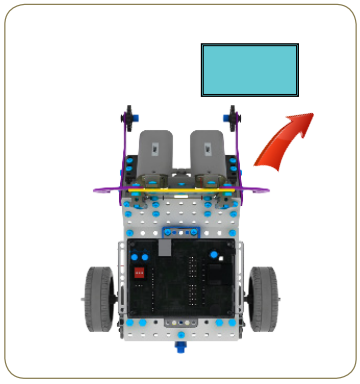
Connect in this order :

1. Connect left DC motor to L–MOTOR connector1.
2. Connect right DC motor to R–MOTOR connector 2.
3. Connect IR sensor1 to INPUT connector1.
4. Connect IR sensor2 to INPUT connector2.
5. Connect Touch sensor to INPUT connector3.
6. Connect battery case to POWER connector.

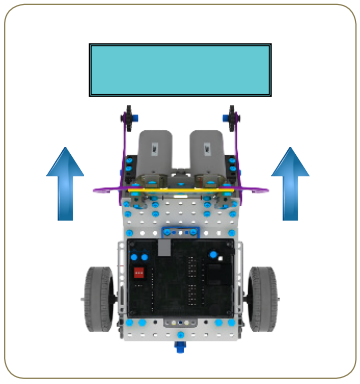
Motion Pattern



1. Recognize left IR sensor, will turn left.



2. Recognize right IR sensor, will turn right.

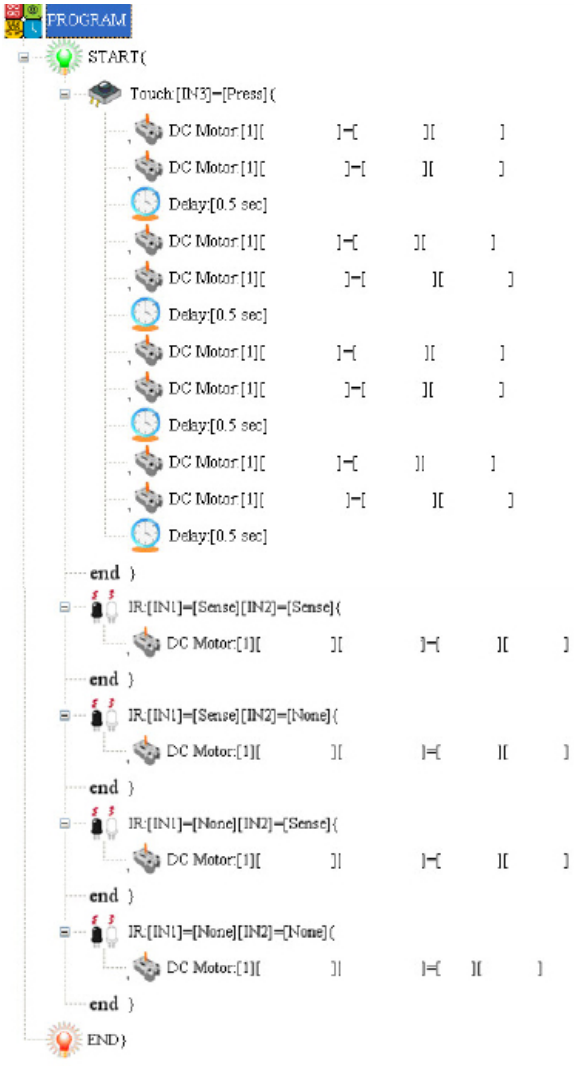


3. Recognize both left and right IR sensor, will go forward.

※ Recognize touch sensor, will go backward.

Learn to compile program in advance

※ Try to write down the program before we compile on software.



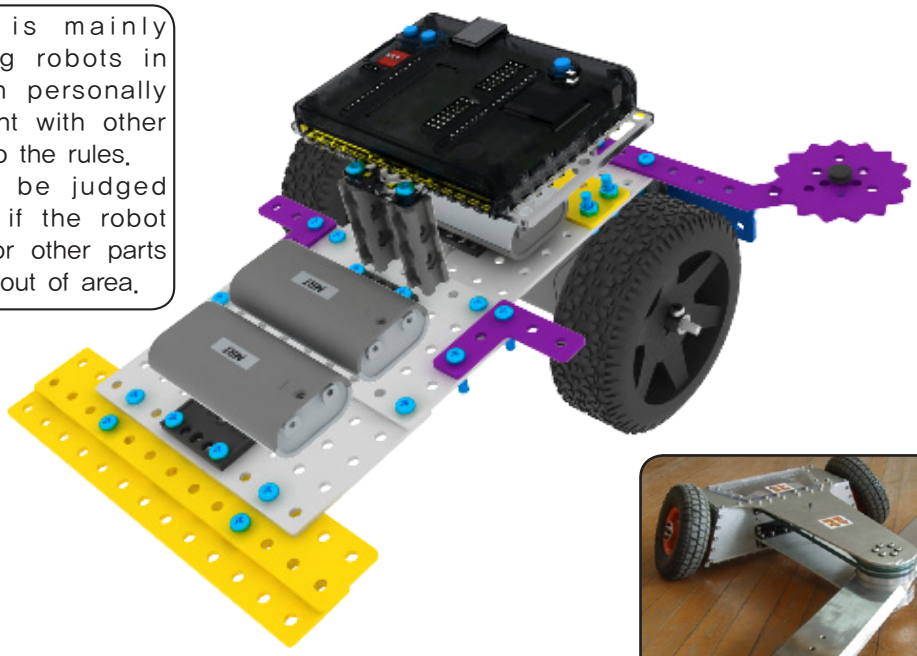
1. Recognize left IR sensor, will turn left.
2. Recognize right IR sensor, will turn right.
3. Recognize both left and right IR sensor, will go forward.
4. Recognize touch sensor, will go backward

Program Download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download to start".
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

BATTLE ROBOT

Battle Robot is mainly used as fighting robots in competition,often personally assembled to fight with other robots according to the rules. The player will be judged loose the game if the robot can't move, arm or other parts damaged or push out of area.



Name	Picture	Quantity
Steel shaft 95mm		2
13AL Frame		1
17AL Frame		3
113AL Frame		2
27AL Frame		2
213AL Frame		2
39AL Frame		2
59AL Frame		2
AL Frame90		2
AL Sprocket		2

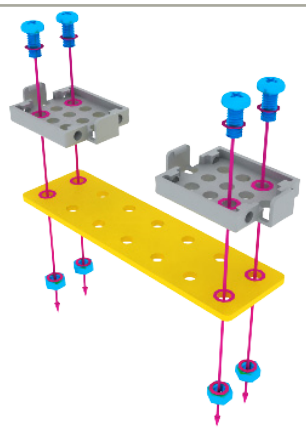
Name	Picture	Quantity
9V Battery Case		1
MRT5-1 Main board		1
DC MOTOR		2
Remote Controller		1
AL Frame135		2
Motor Mount		3

Name	Picture	Quantity
Bolt 8mm		30
Bolt 16mm		22
Nut		40
ABS Connecting shaft		2
B-Bush		2
Guide Wheel		2
L-Gear		2
Sleeve pipe		4
Big Wheel2		2
RC Receiver		1
4-5 Pillar block		2
2-3 Pillar Block		5

1

8mm X4

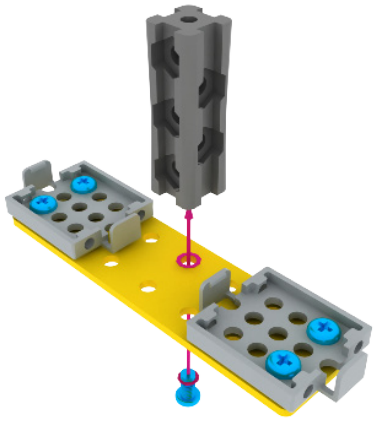
X4



1:1

2

8mm X1

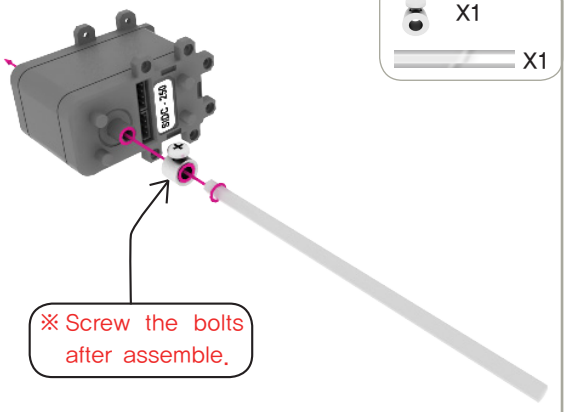


1:1

3

X1

X1



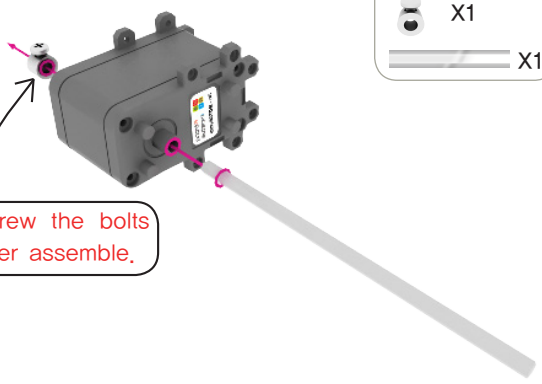
※ Screw the bolts after assemble.

95mm

4

X1

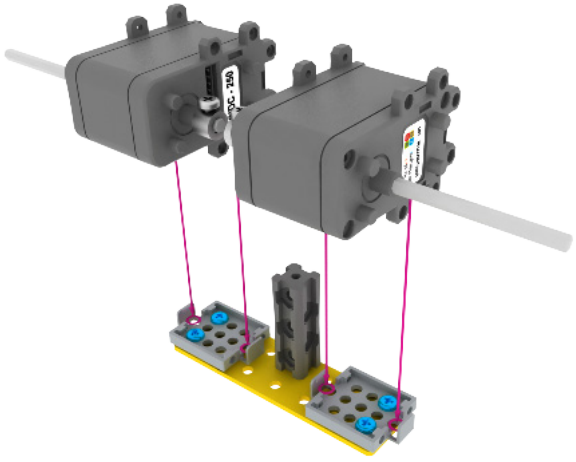
X1



※ Screw the bolts after assemble.

95mm

5



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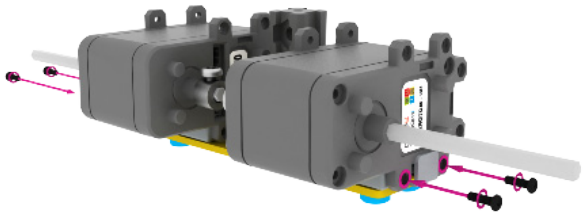
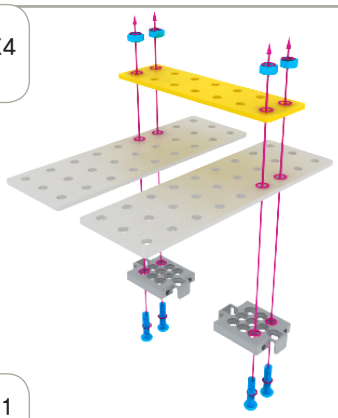


7

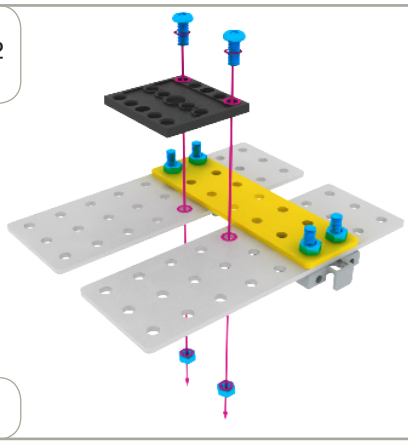
16mm X4
X4



1:1

8

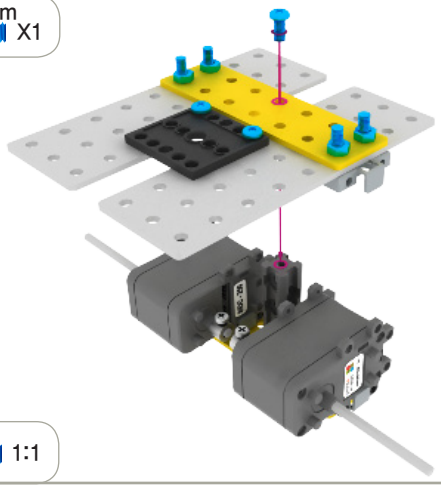
8mm X2
X2



1:1

9

8mm X1



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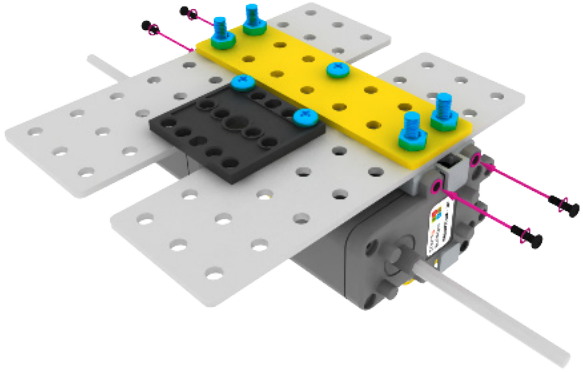
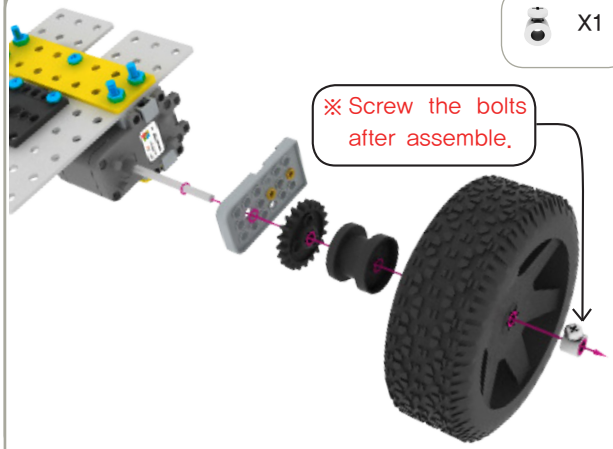
10



11 Assemble left wheel

X1

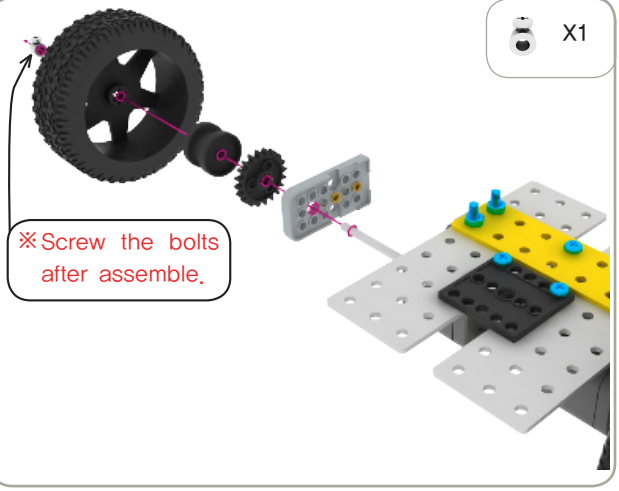
※ Screw the bolts after assemble.



12 Assemble right wheel

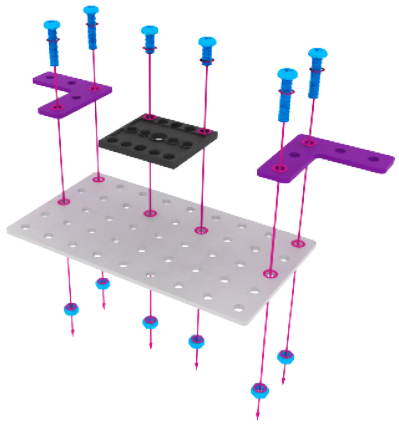
X1

※ Screw the bolts after assemble.



13

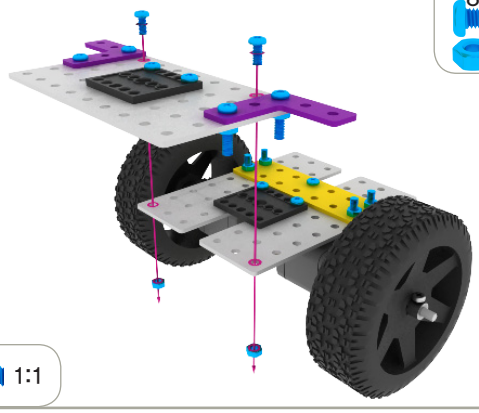
16mm X4
8mm X2
X6



1:1
1:1

14

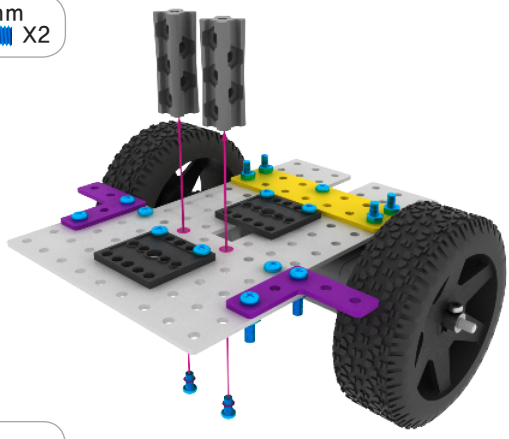
8mm X2
X2



1:1

15

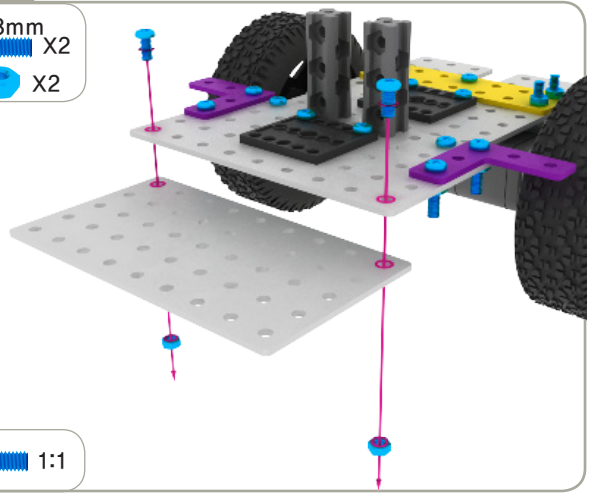
8mm X2



1:1

16

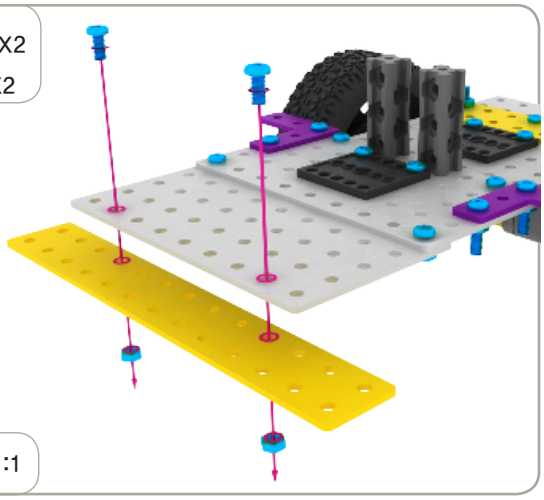
8mm X2
X2



1:1

17

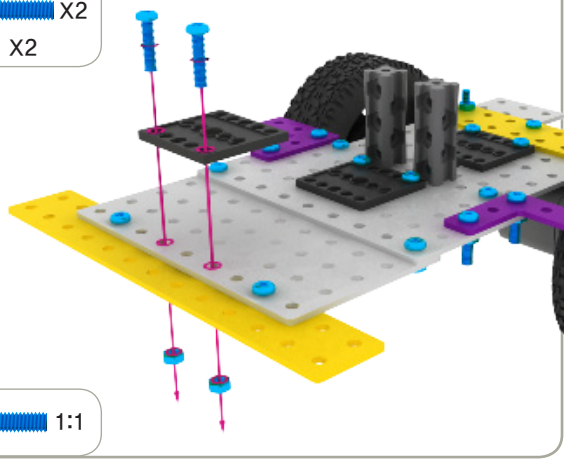
8mm X2
X2



1:1

18

16mm X2
X2



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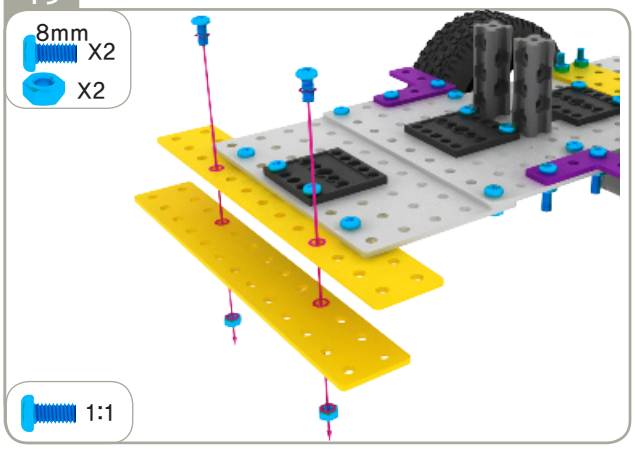
19



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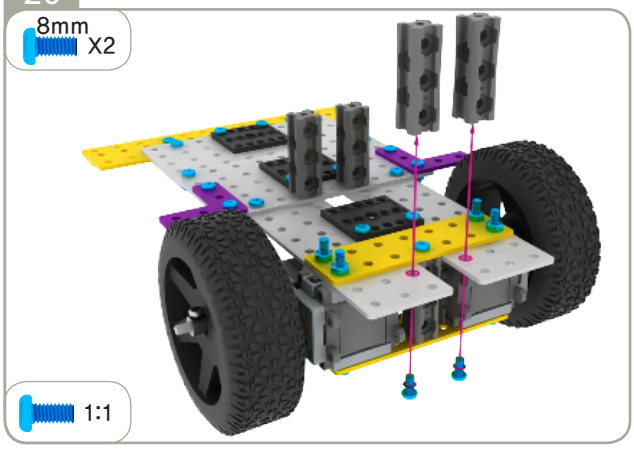

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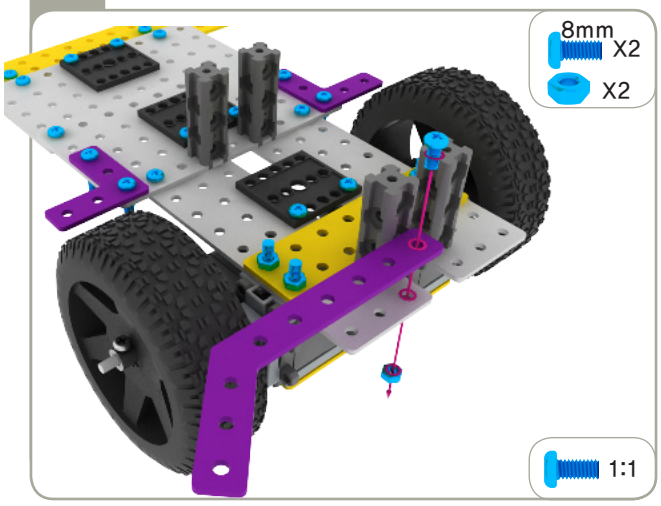

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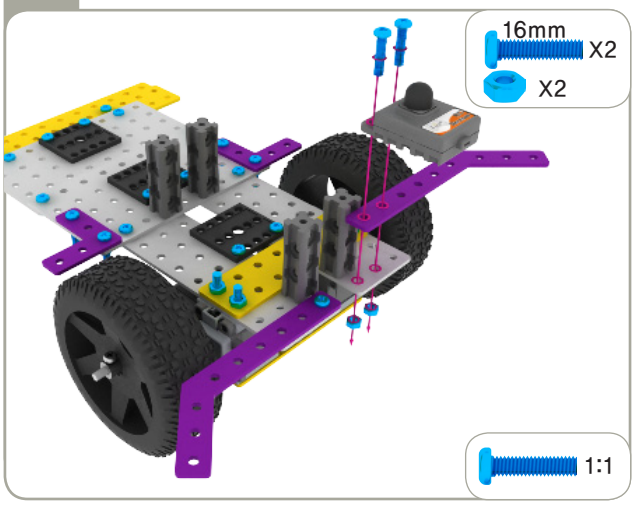

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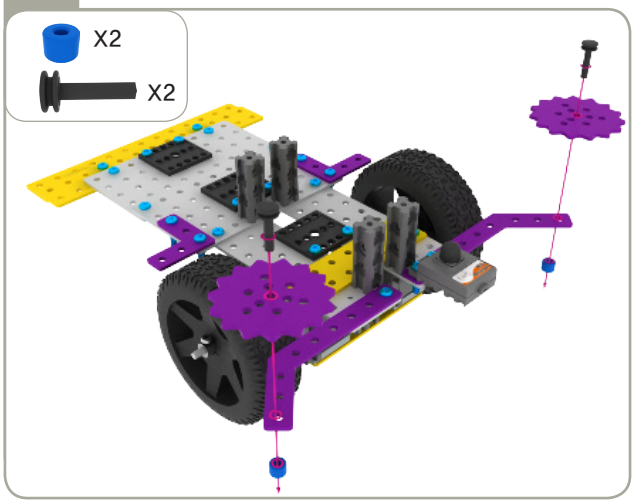

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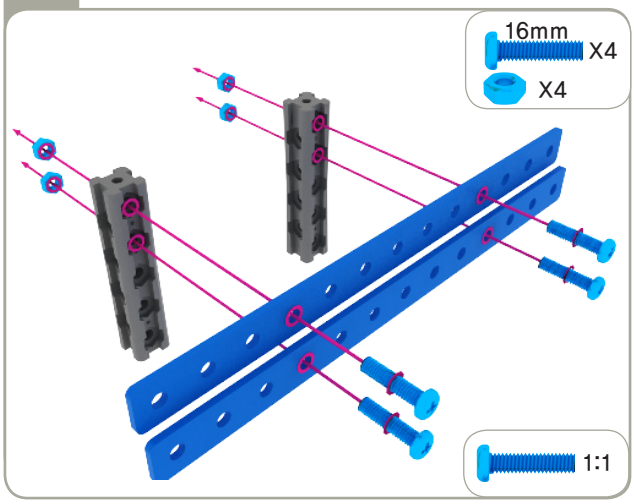

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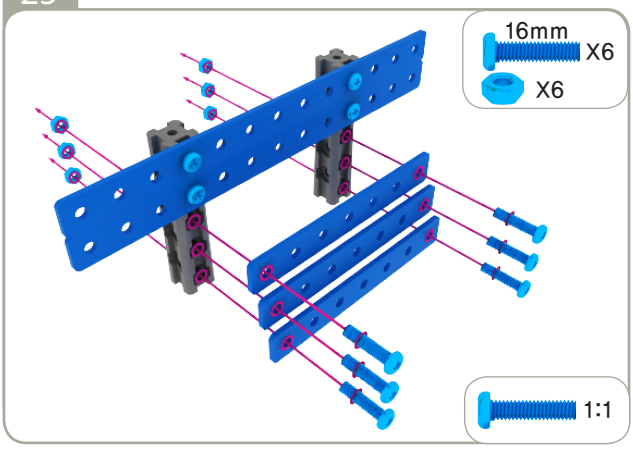

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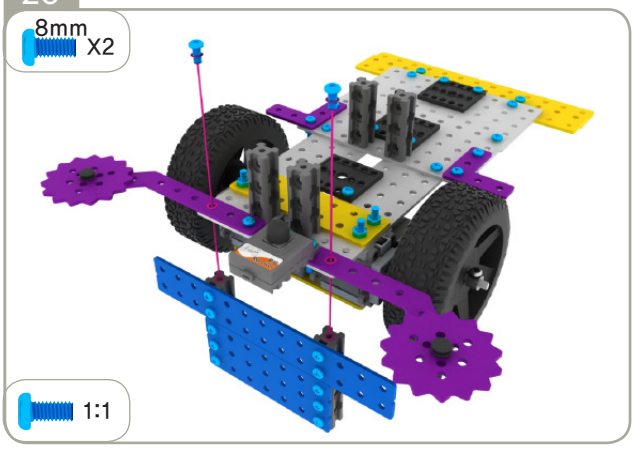

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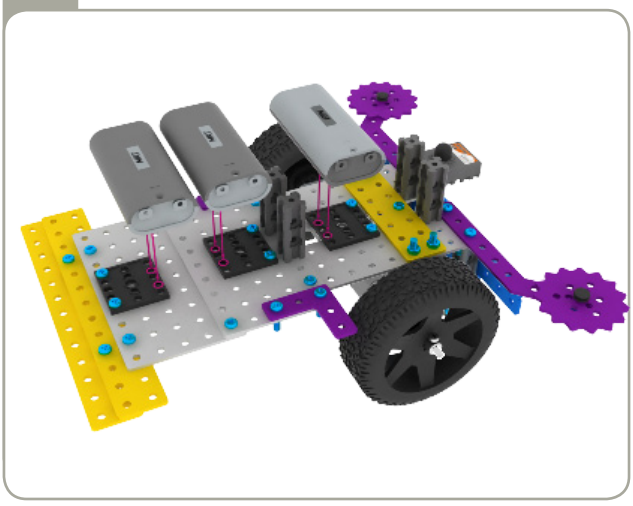

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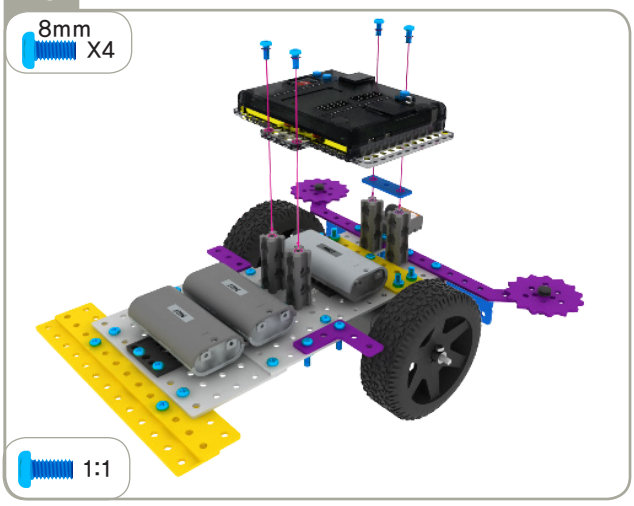
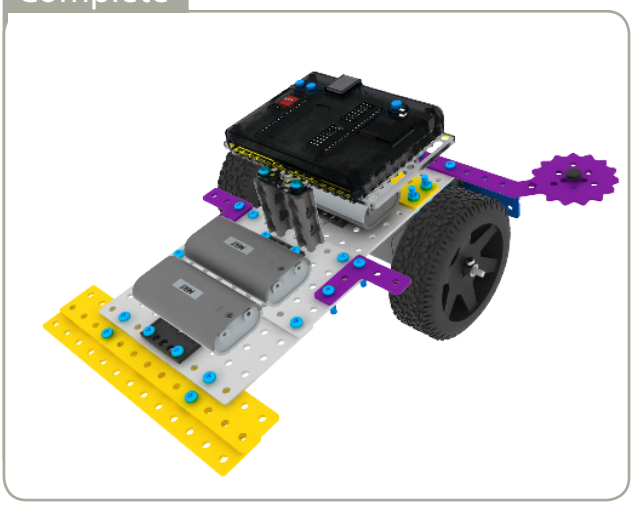
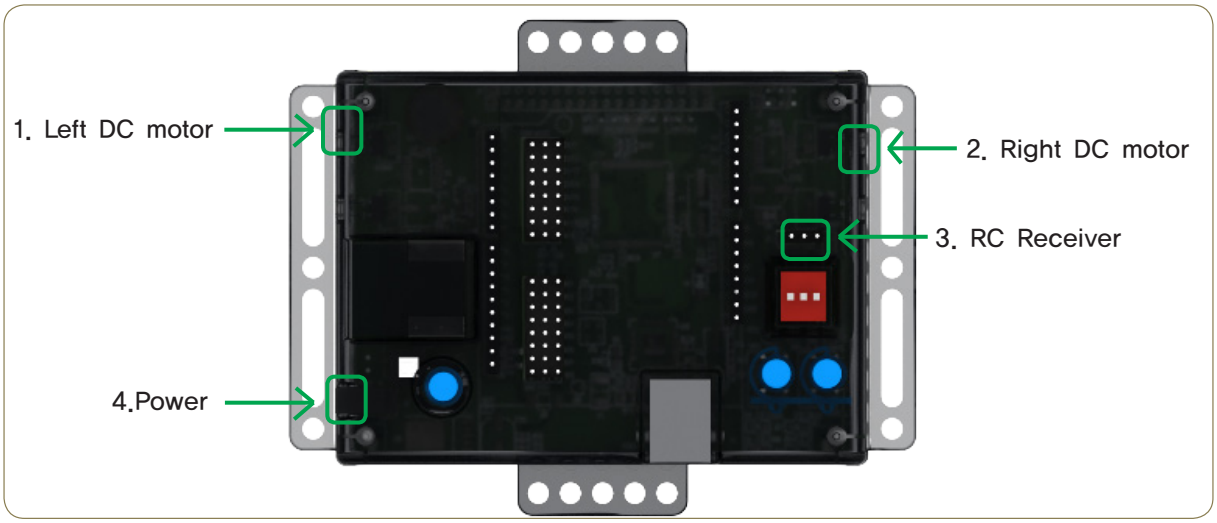


Complete



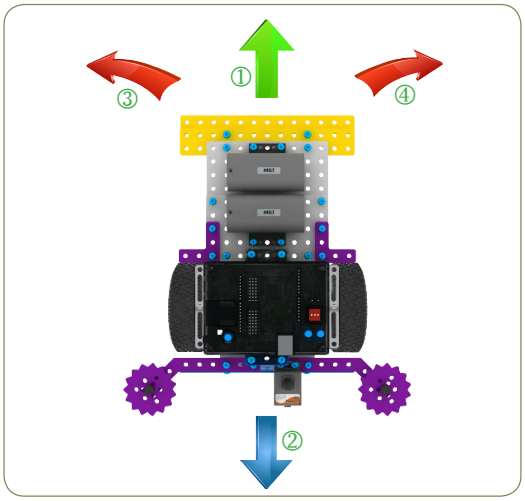
Connecting the mainboard



Please connect in this order:

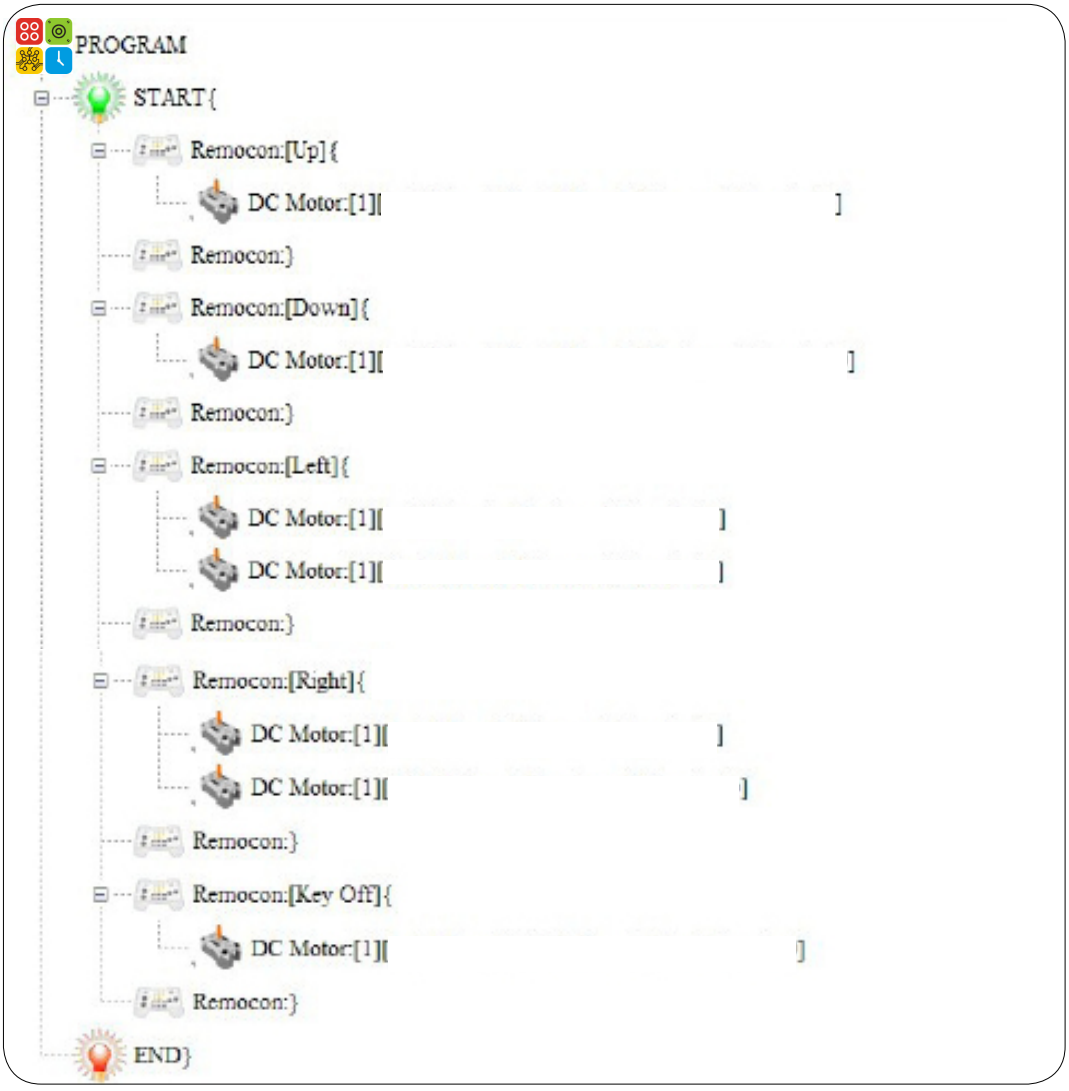
1. Connect left DC motor to L–MOTOR connector.
2. Connect right DC motor to R–MOTOR connector.
3. Connect RC Receiver to R/C connector.
4. Connect battery case to Power connector.

Motion Pattern



Learn to compile program in advance

※ Try to write down the program before we compile on software.



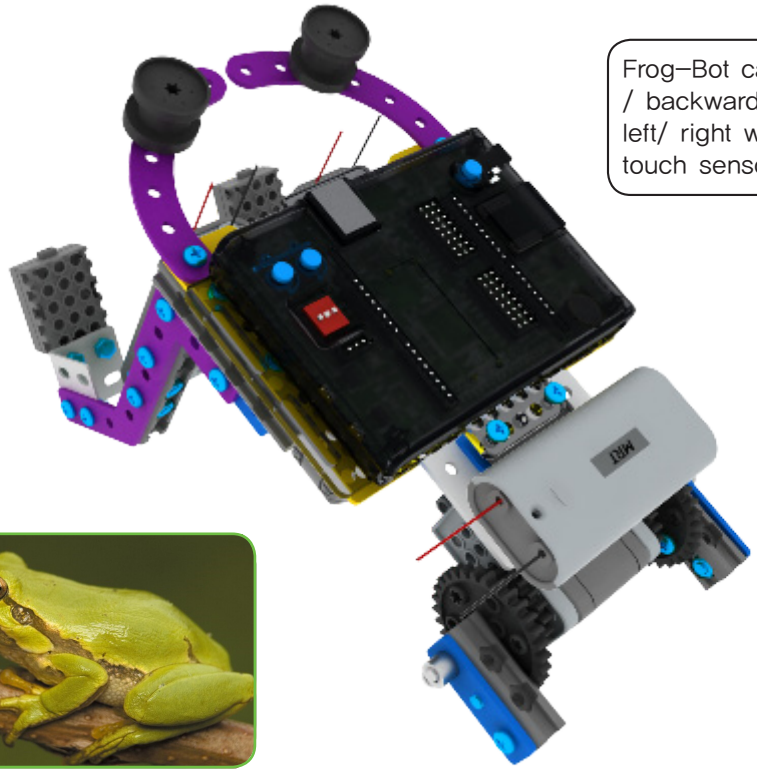
1. Press the directional key (up/down) of remote controller, the robot will move forward and backward.
2. Press the directional key (left / right) of remote controller, the robot will move left and right .
3. It's possible to compile the program as your idea, like press "up" and "left/right" together or press "down" and "left/right"together.

※ Program example : Refer to the back of book.

Program download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download to start".
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

FROG-BOT



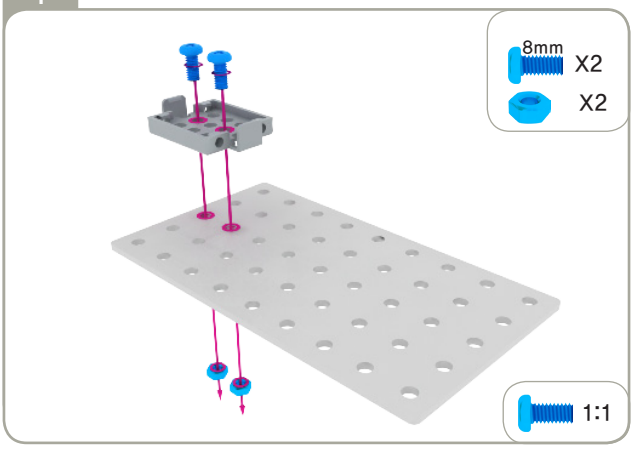
Frog–Bot can go forwarder / backward, also can turn left/ right when recognize touch sensor.

Name	Picture	Quantity
Steel shaft 95mm		1
Steel shaft 20mm		1
13AL Frame		5
17AL Frame		2
27AL Frame		2
59AL Frame		1
4–5 Pillar block		4
2–3 Pillar Block		2
Motor Mount		3

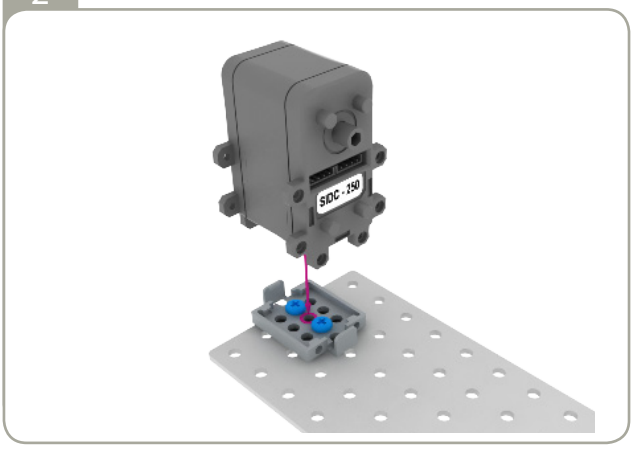
Name	Picture	Quantity
9V Battery Case		1
MRT5–1 Main board		1
DC MOTOR		2
AL Frame 90		2
AL Round Block		2
AL Frame 135		2

Name	Picture	Quantity
Bolt 8mm		20
Bolt 16mm		22
Bolt 20mm		2
Nut		44
ABS Connecting shaft		2
Half–Bush		2
Guide Wheel		2
M–Gear		2
L–Gear		2
Sleeve pipe		4
Big Wheel1		2
Touch Sensor		2
D90 S–Bracket		2

1


8mm X2
X2
1:1

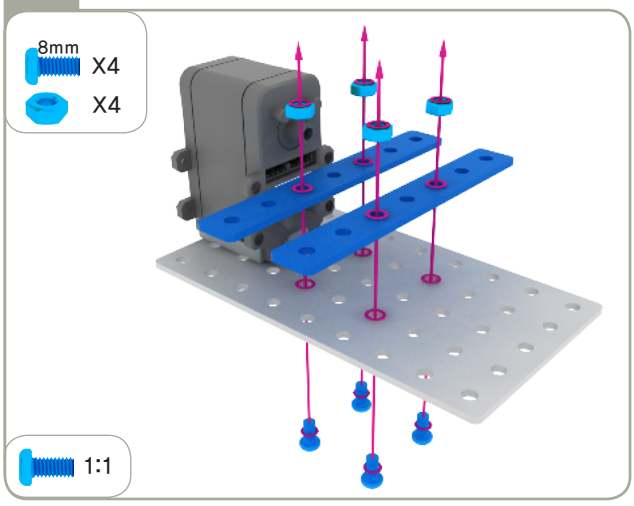
2


SIDC - 250

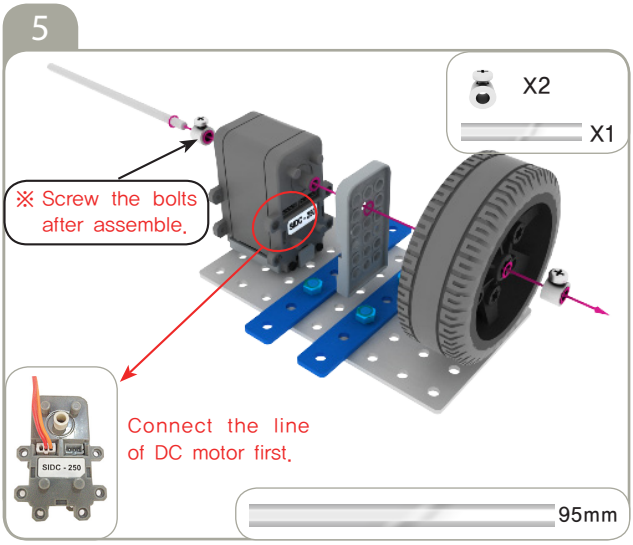
3


SIDC - 250

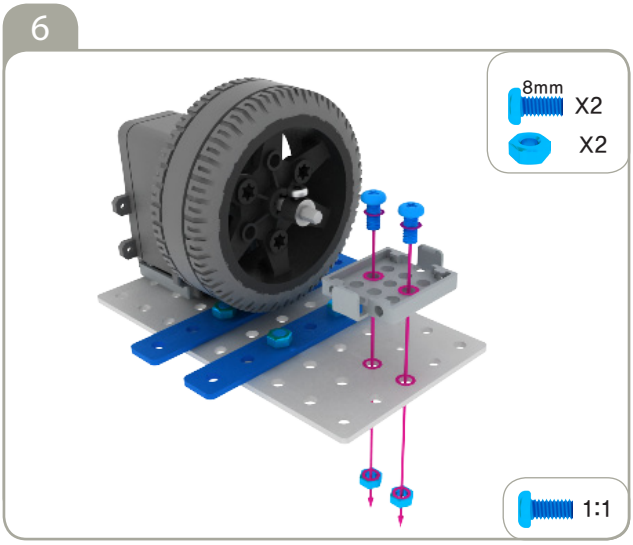
4


8mm X4
X4
1:1

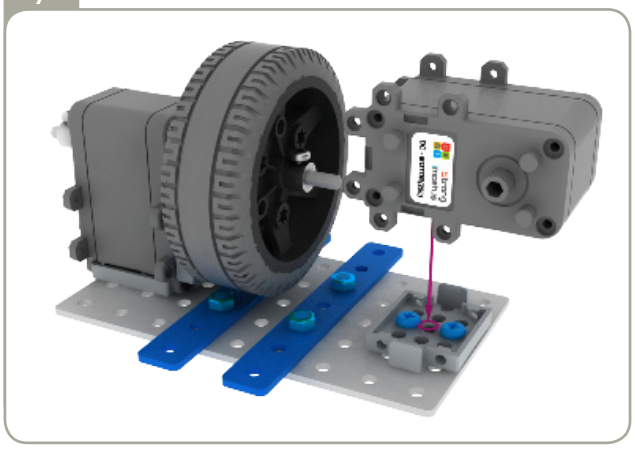
5


X2
X1
※ Screw the bolts after assemble.
Connect the line of DC motor first.
95mm

6


8mm X2
X2
1:1

7



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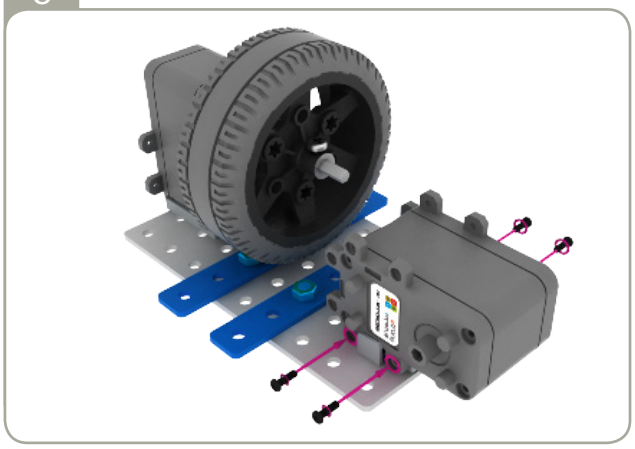

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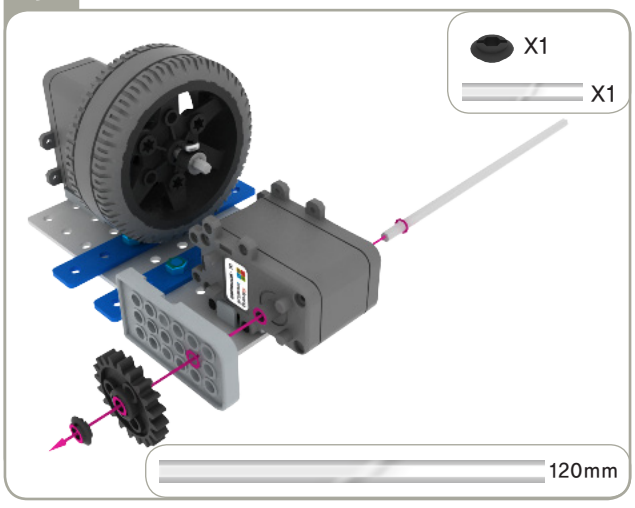
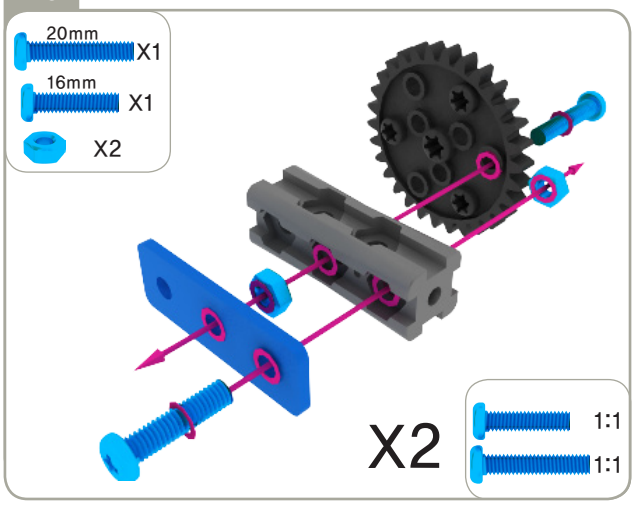
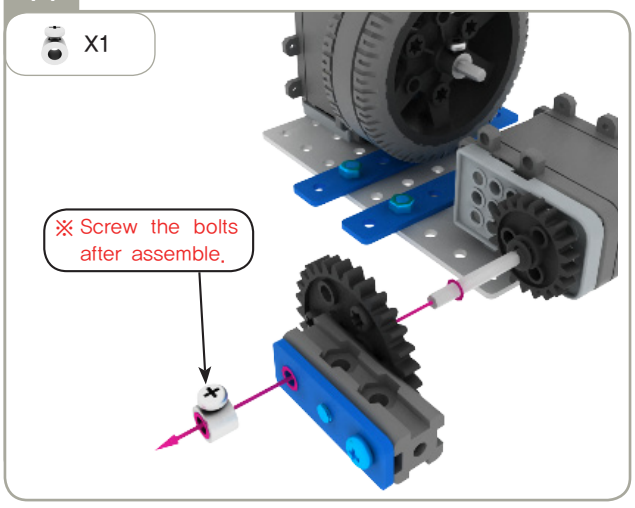

X1
X1
120mm

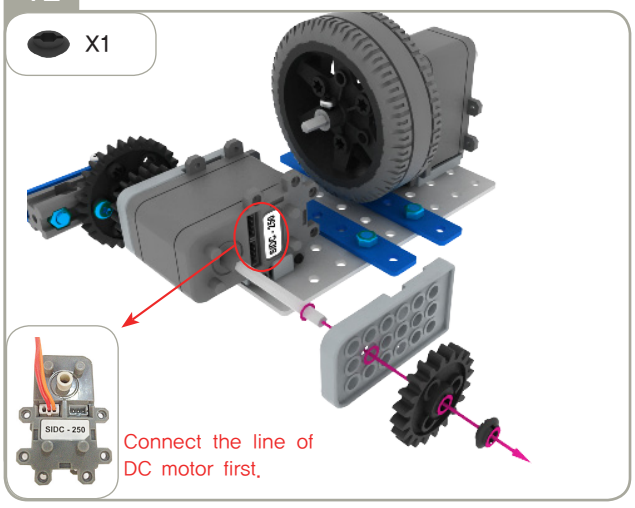
10


20mm
X1
16mm
X1
X2
X2
1:1
1:1

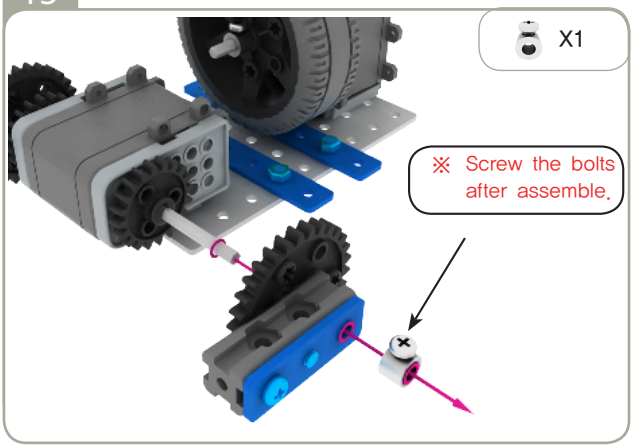
11


X1
※ Screw the bolts after assemble.

12


X1
SIDC - 250
Connect the line of DC motor first.

13



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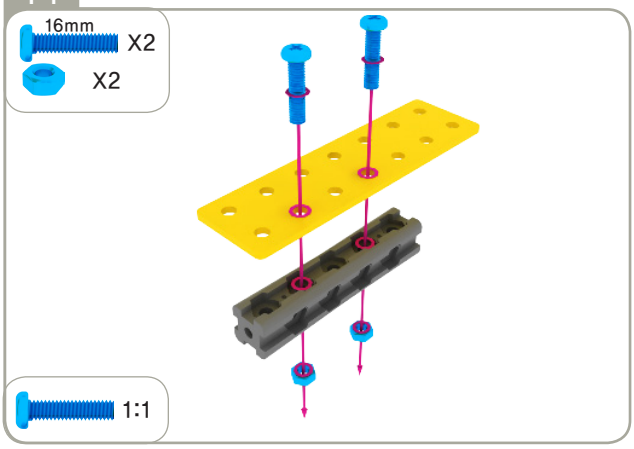

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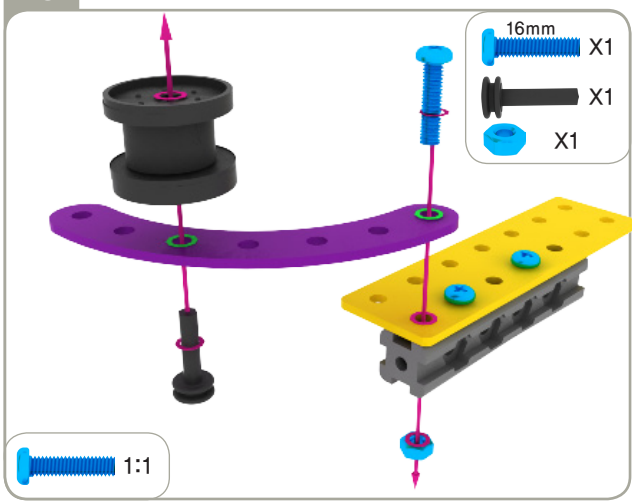

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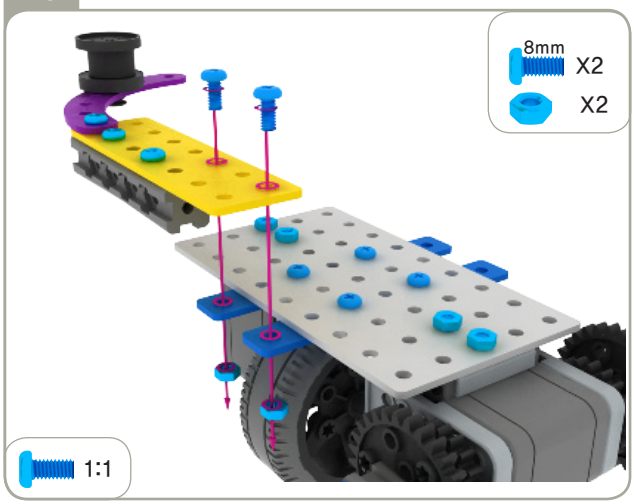
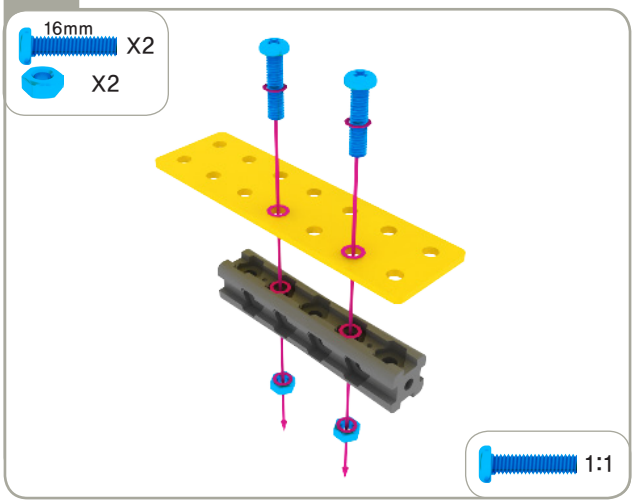
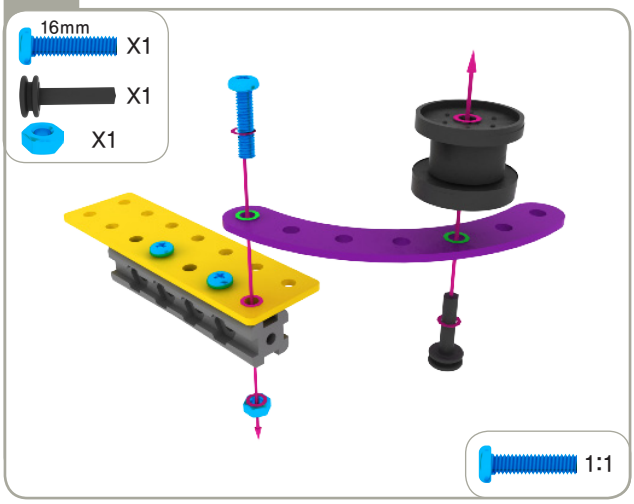


17

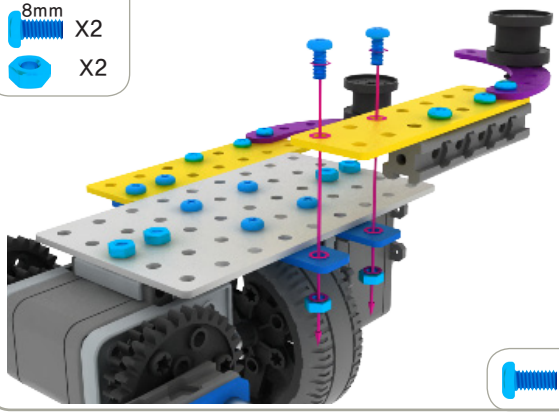


18



19

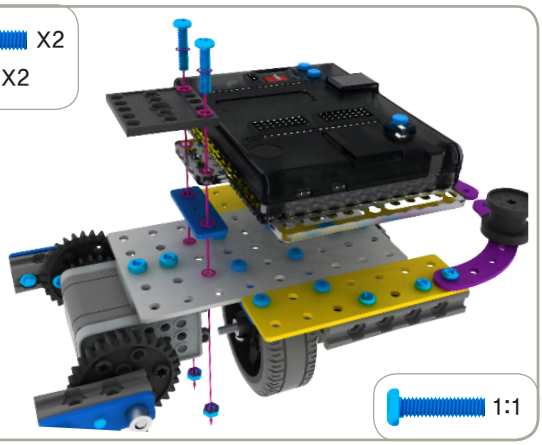
8mm X2
X2



1:1

20

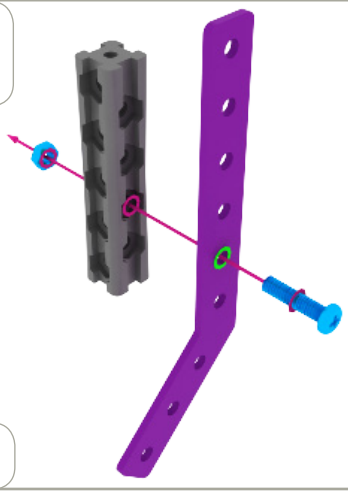
16mm X2
X2



1:1

21

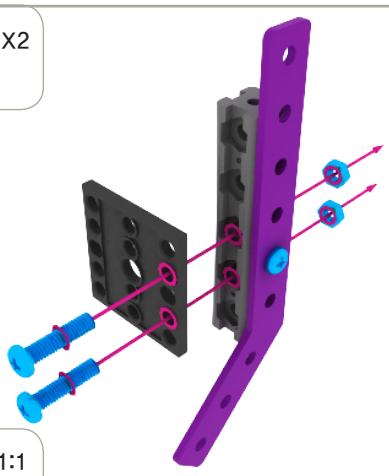
16mm X1
X1



1:1

22

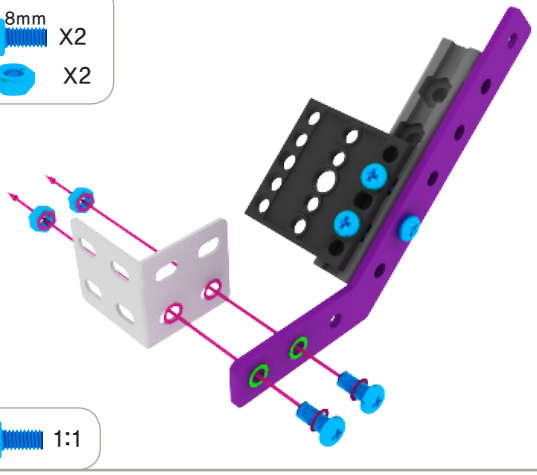
16mm X2
X2



1:1

23

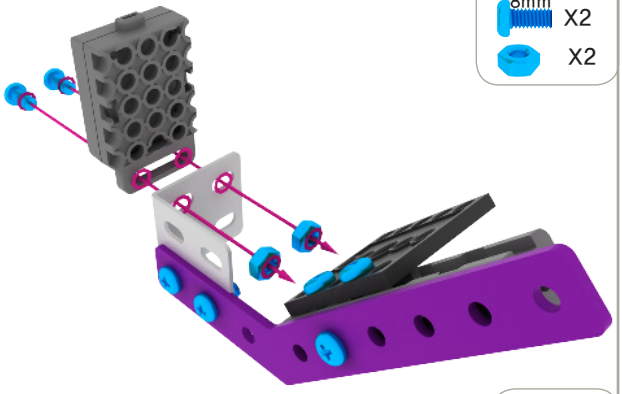
8mm X2
X2



1:1

24 Assemble touch sensor.

8mm X2
X2

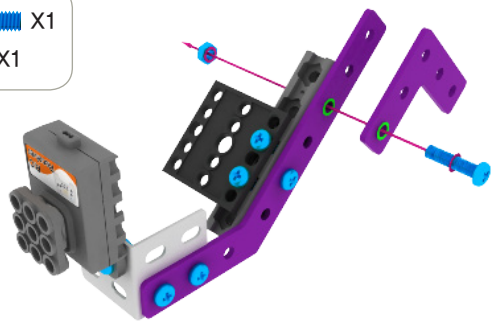


1:1

25

16mm X1

X1

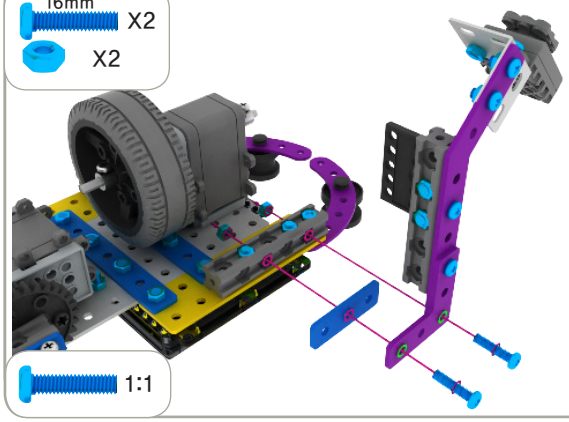


1:1

26

16mm X2

X2

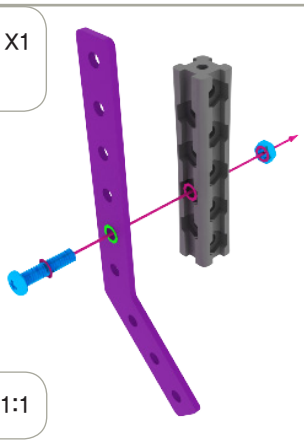


1:1

27

16mm X1

X1

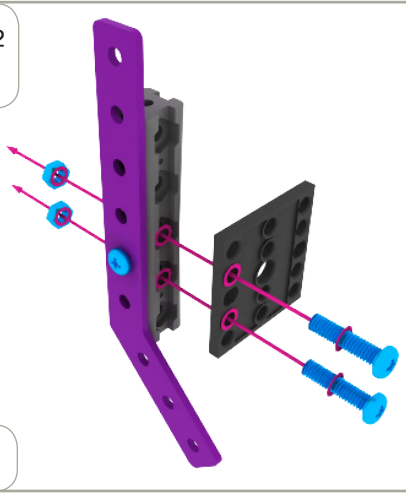


1:1

28

16mm X2

X2

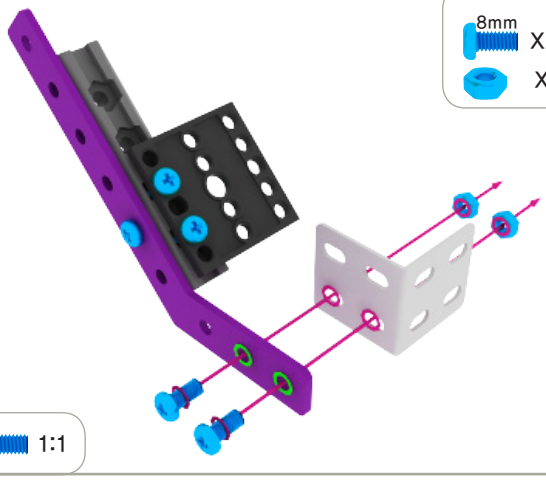


1:1

29

8mm X2

X2

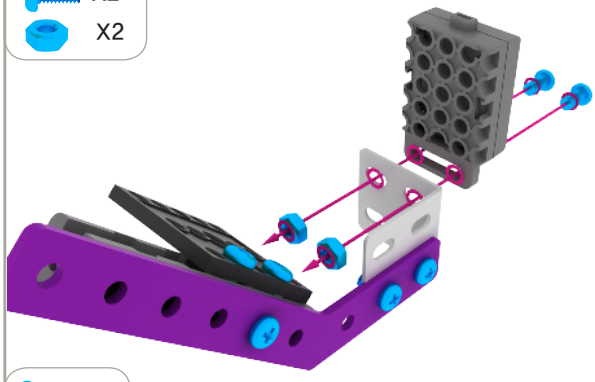


1:1

30 assemble touch sensor.

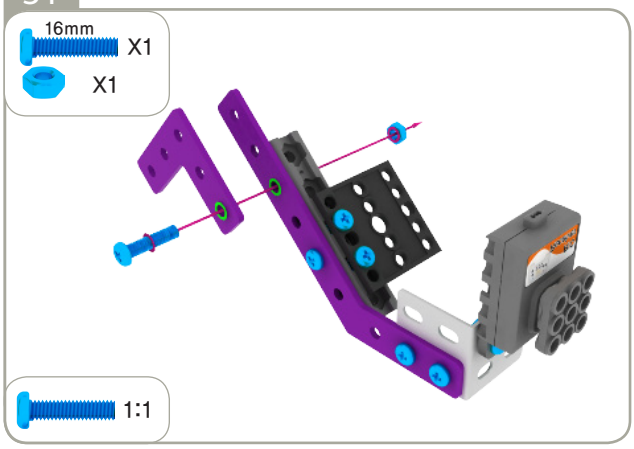
8mm X2

X2



1:1

31



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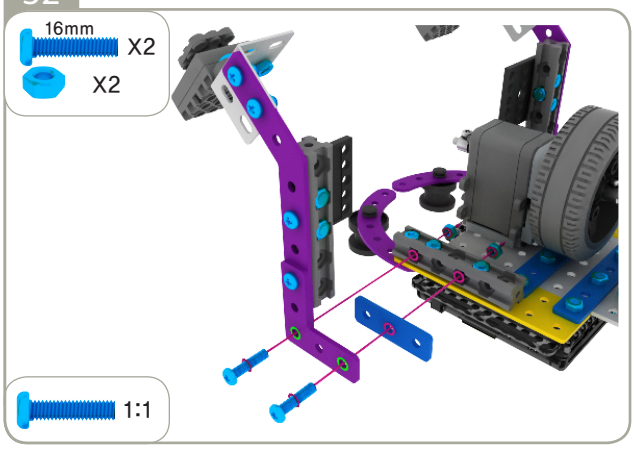

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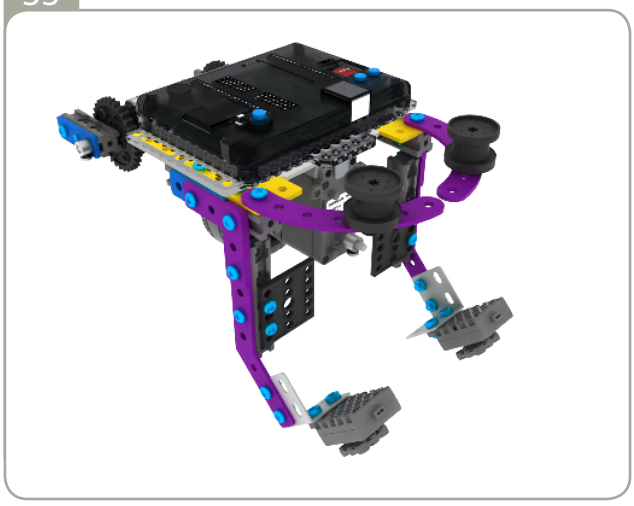
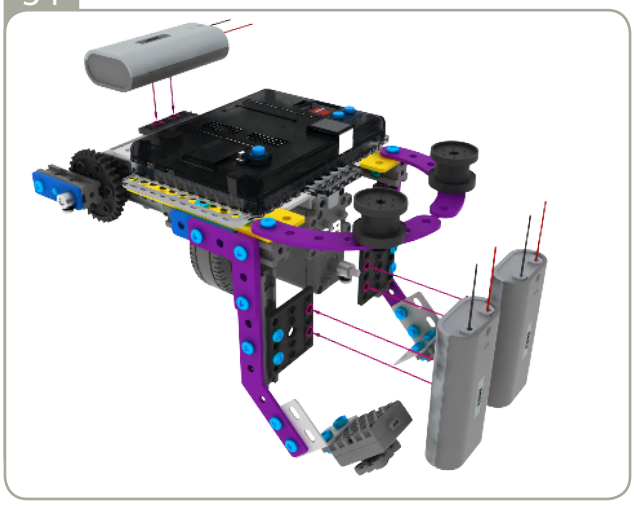
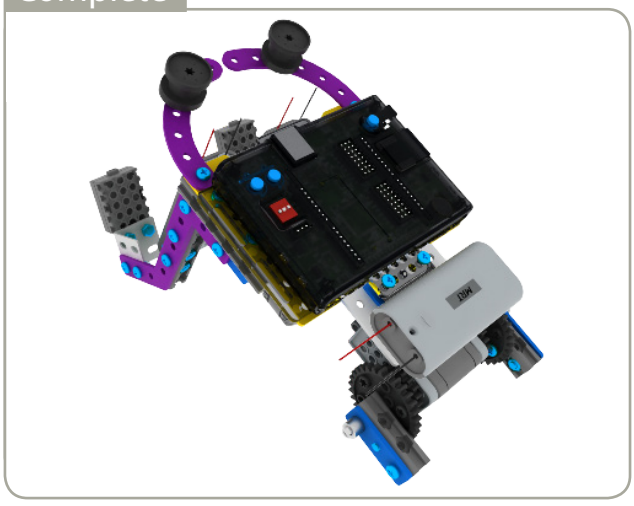


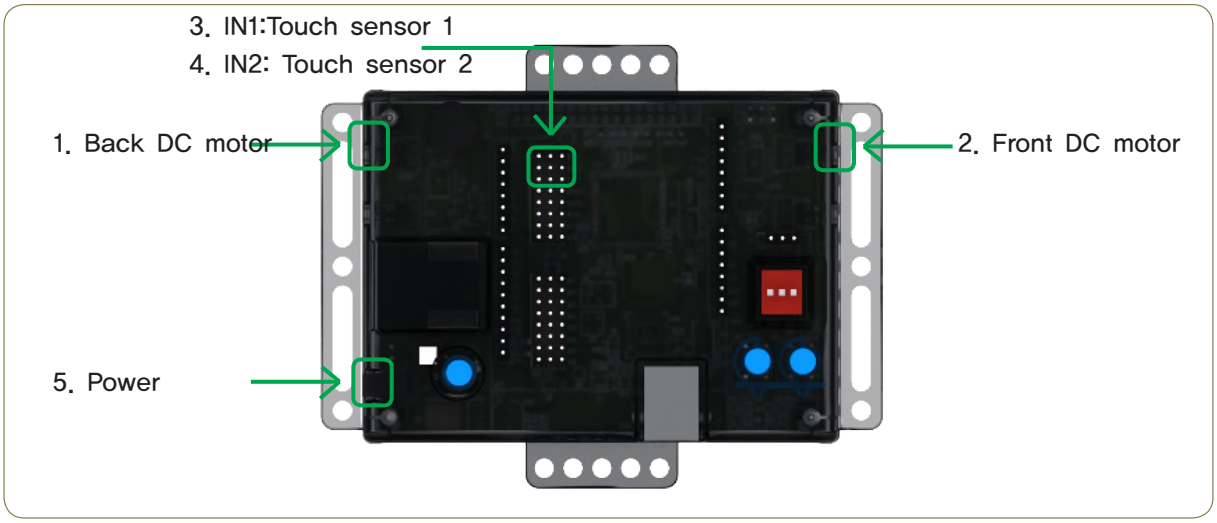
34



Complete



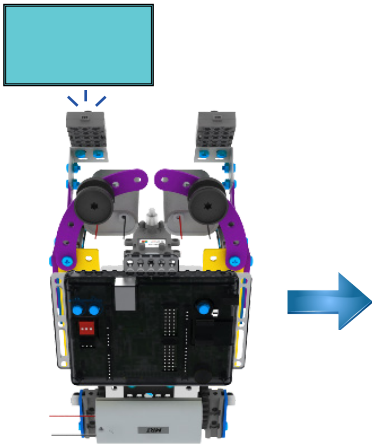
Connecting the mainboard



Please connect in this order:

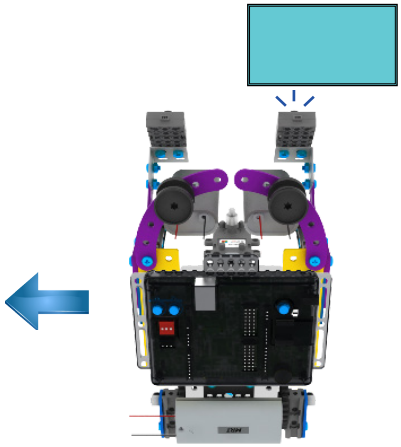
1. Connect left DC motor to L–MOTOR connector1.
2. Connect right DC motor to R–MOTOR connector2.
3. Connect Touch sensor1 to INPUT1 connector.
4. Connect Touch sensor2 to INPUT2 connector.
5. Connect battery case to Power connector.

Motion Pattern



[Recognize left touch sensor]

1. Go Backward for a while
2. Turn right

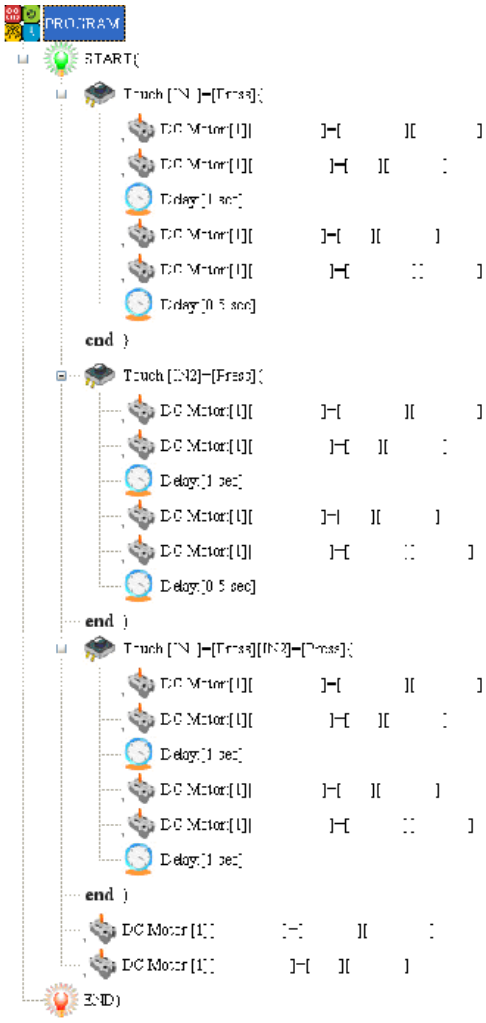


[Recognize right touch sensor]

1. Go backward for a while
2. Turn left

Learn to compile program in advance

Try to write down the program before we compile on software.



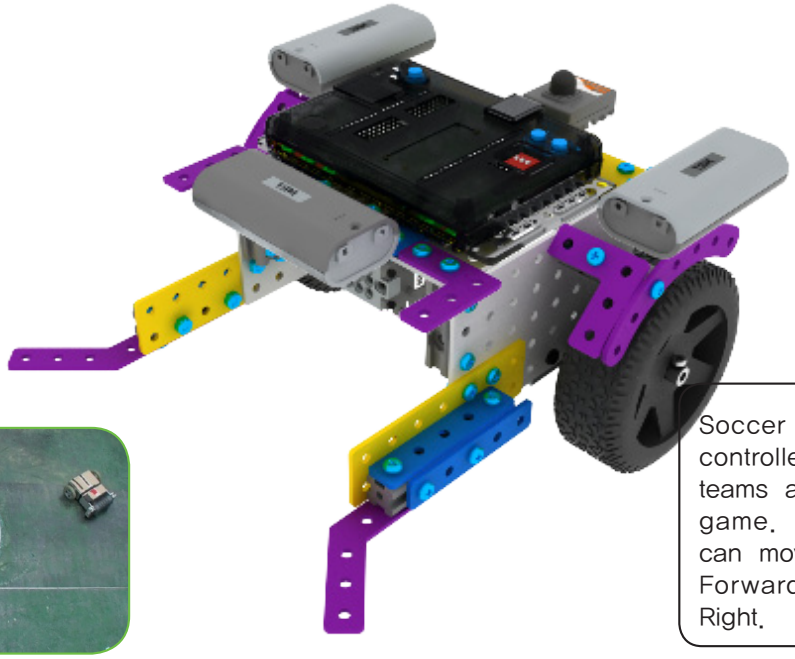
1. Recognize nothing, the robot go forward.
2. Recognize left touch sensor and back for a while then turn right to go ahead, back for a while
3. It's possible to compile the program as your idea, like press "up" and "left/right" together or press "down" and "left/right"together.

※ Program example : Refer to the back of book.

Program download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download to start".
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

Soccer Robot



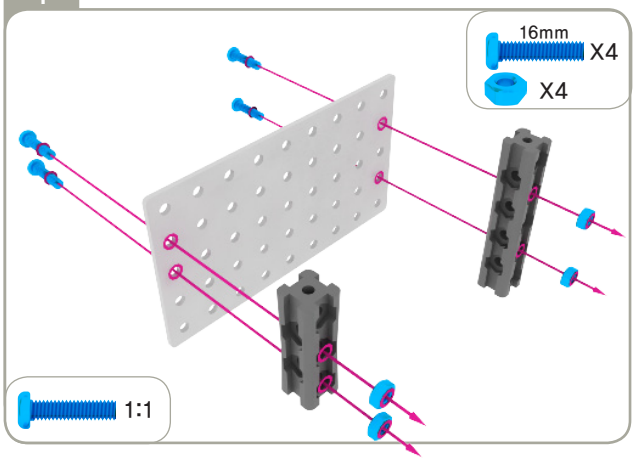
Soccer Robot with remote controller, divided into two teams and play the soccer game. The Soccer Robot can move in 4 directions : Forward/ Backward, Left/ Right.

Name	Picture	Quantity
Steel shaft 95mm		2
27AL Frame		2
213AL Frame		1
39AL Frame		2
AL Frame 135		2
59AL Frame		2
MRT5–1 Main board		1

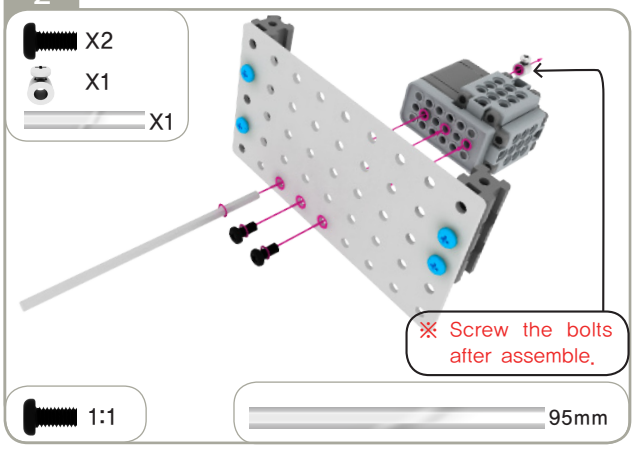
Name	Picture	Quantity
9V Battery Case		1
IR RC Receiver		1
DC MOTOR		2
Remote Controller		1
AL Frame 90		4
15AL Frame		4
17AL Frame		2
AL Round Block		2

Name	Picture	Quantity
Bolt		4
Bolt 8mm		20
Bolt 16mm		18
Bolt 20mm		8
Nut		38
S–Gear		2
Guide Wheel		2
L–Gear		2
4–5 Pillar block		4
2–3 Pillar Block		4
Sleeve pipe		4
Motor Mount		3
Big Wheel2		2

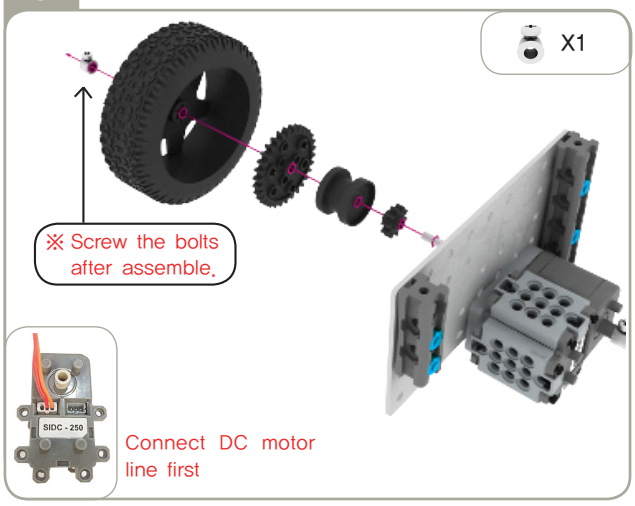
1


16mm
X4
X4
1:1

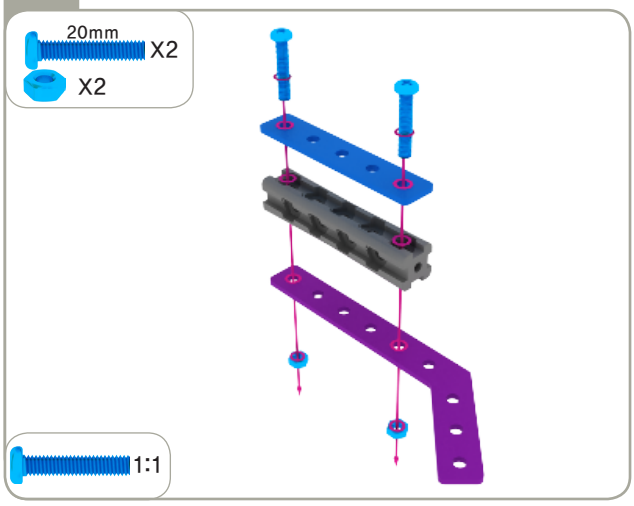
2


X2
X1
X1
※ Screw the bolts after assemble.
1:1
95mm

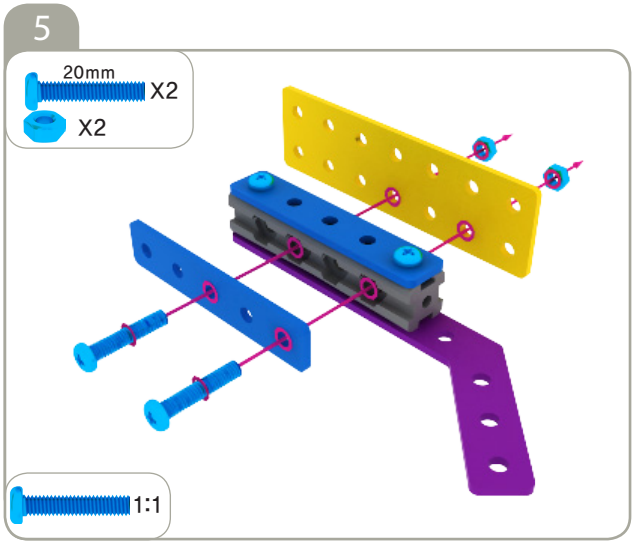
3


X1
※ Screw the bolts after assemble.
SIDC - 250
Connect DC motor line first

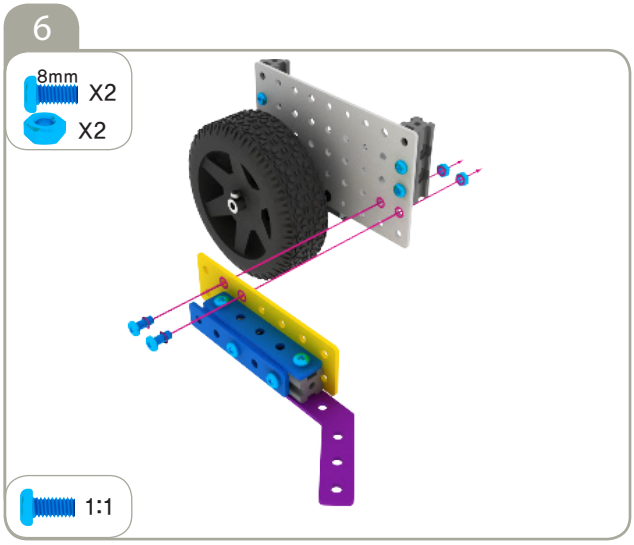
4


20mm
X2
X2
1:1

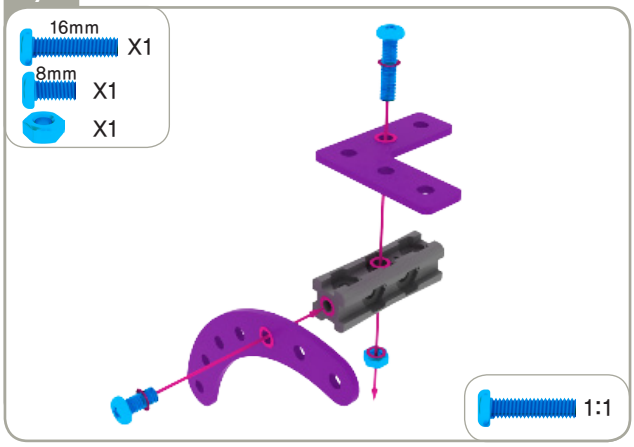
5


20mm
X2
X2
1:1

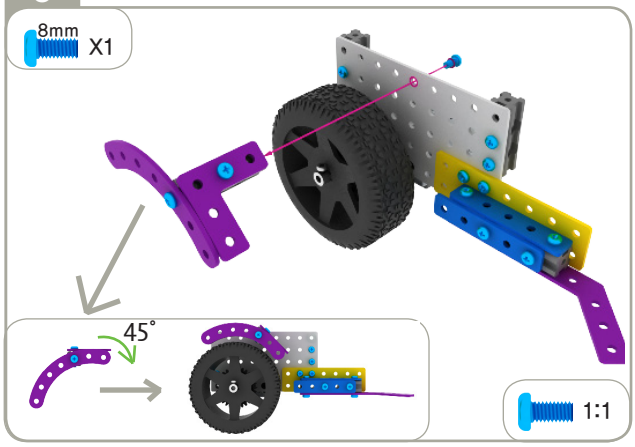
6


8mm
X2
X2
1:1

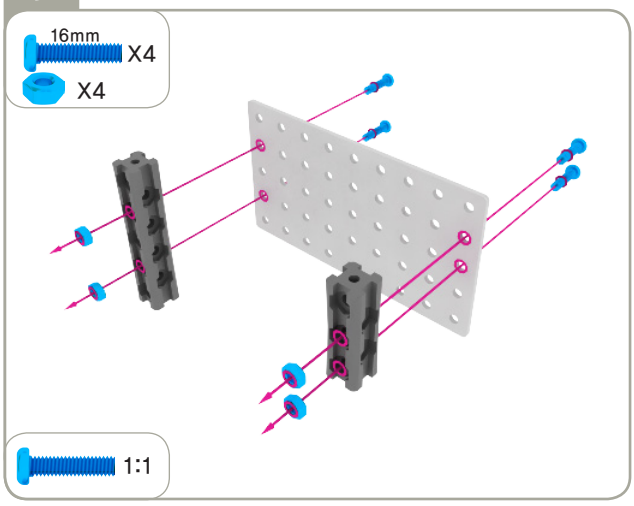
7


16mm
X1
8mm
X1
X1
1:1

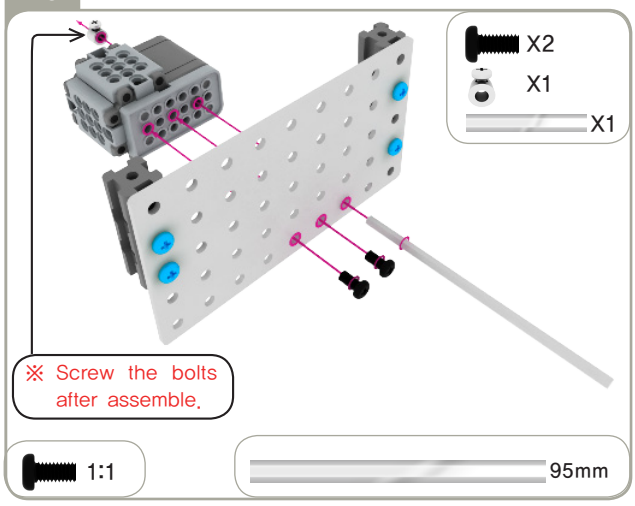
8


8mm
X1
45°
1:1

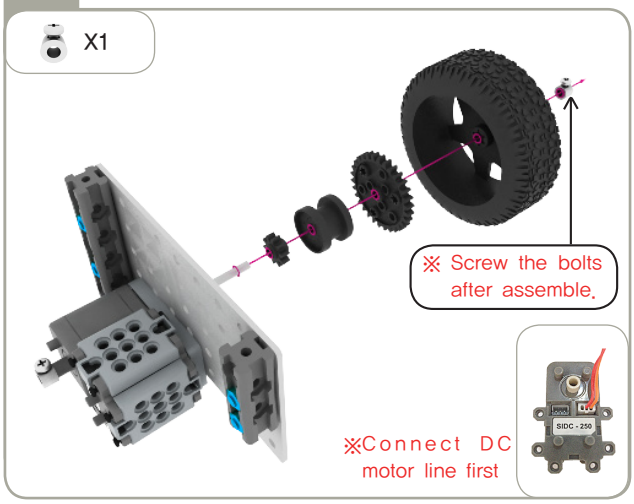
9


16mm
X4
X4
1:1

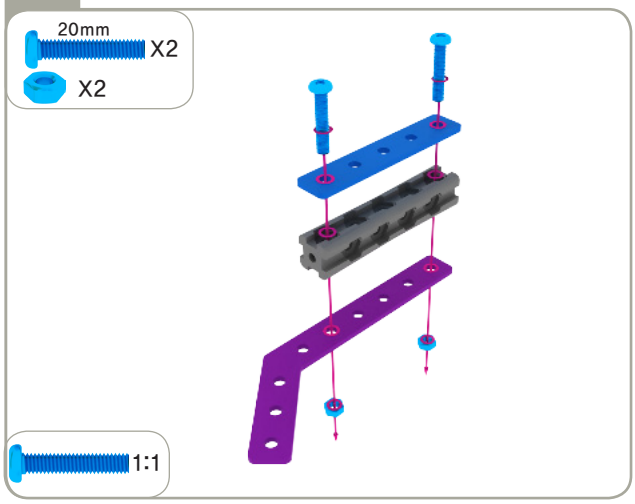
10


X2
X1
X1
※ Screw the bolts after assemble.
1:1
95mm

11

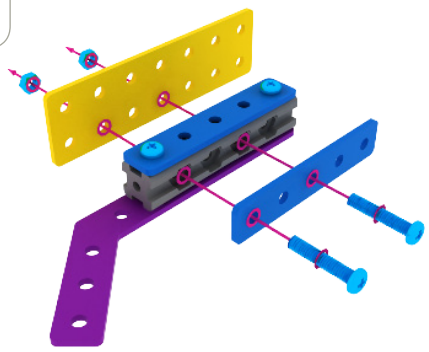

X1
※ Screw the bolts after assemble.
※Connect DC motor line first

12


20mm
X2
X2
1:1

13

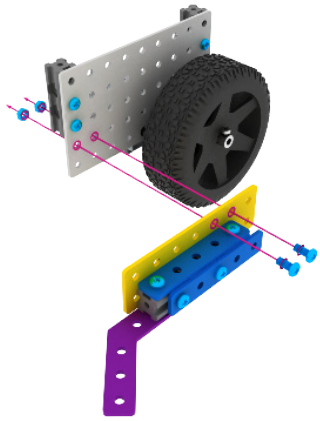
20mm X2
X2



1:1

14

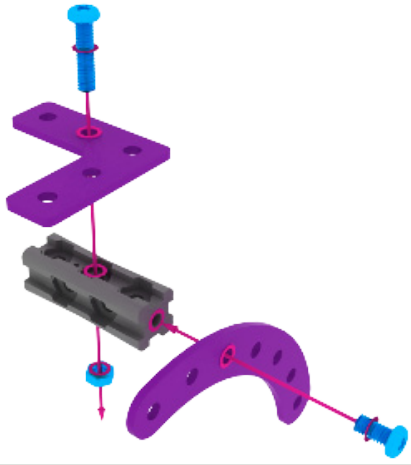
8mm X2
X2



1:1

15

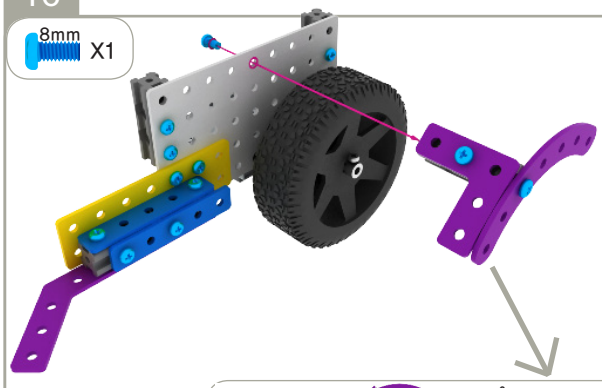
16mm X1
8mm X1
X1



1:1

16

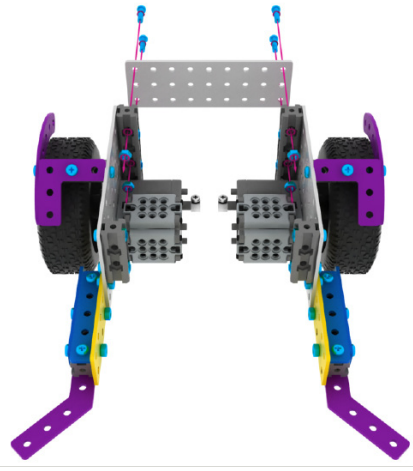
8mm X1



1:1

17

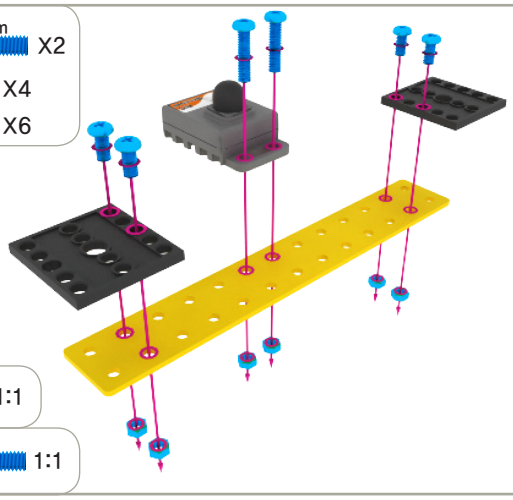
16mm X4
X4



1:1

18

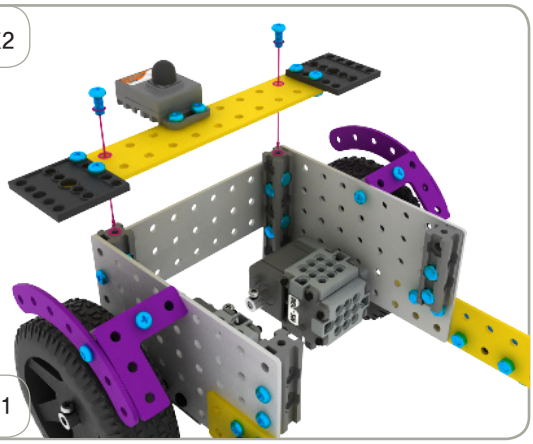
16mm X2
8mm X4
X6



1:1
1:1

19

8mm X2

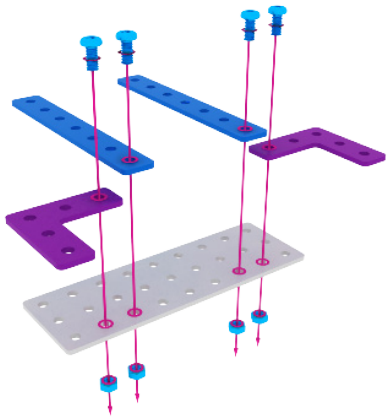


1:1

20

8mm X4

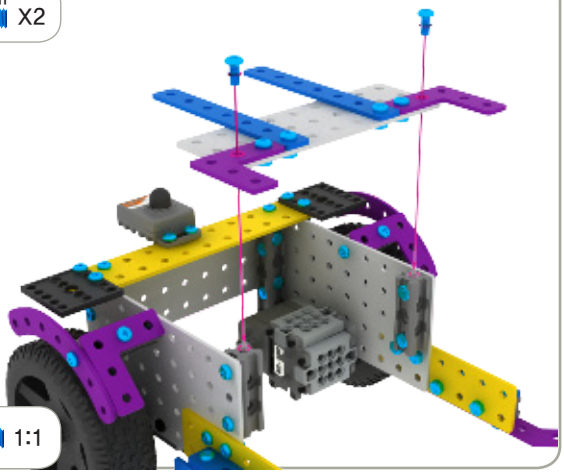
X4



1:1

21

8mm X2

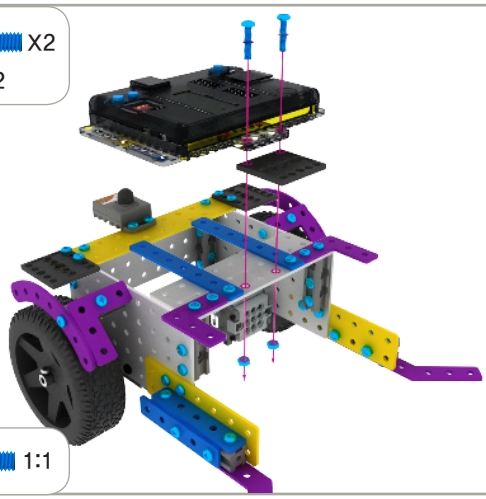


1:1

22

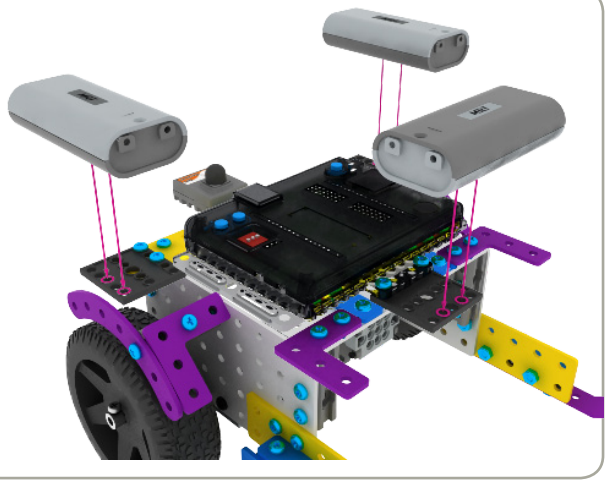
16mm X2

X2

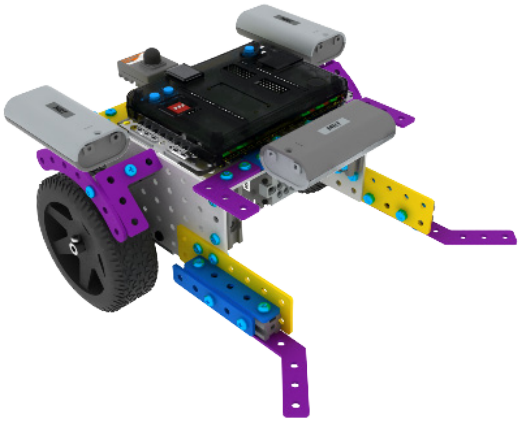


1:1

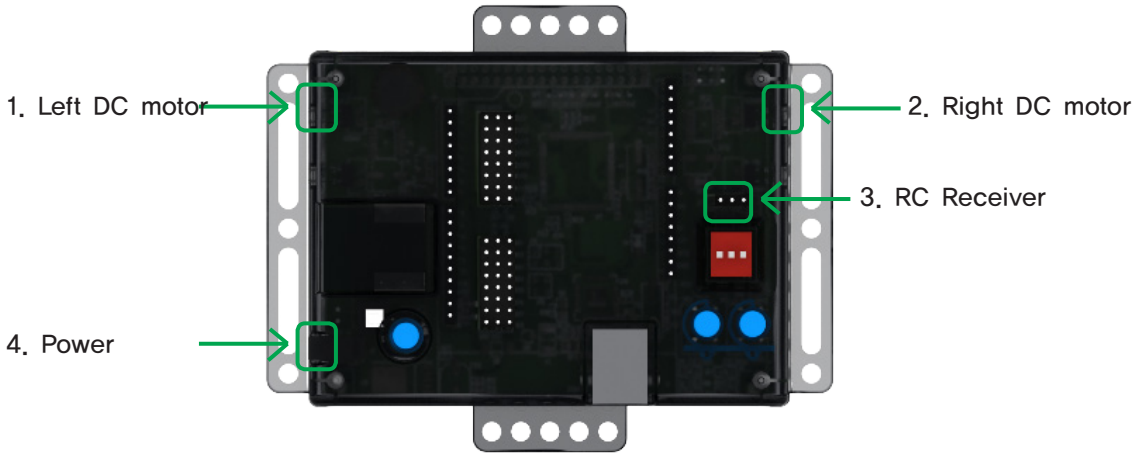
23



Complete



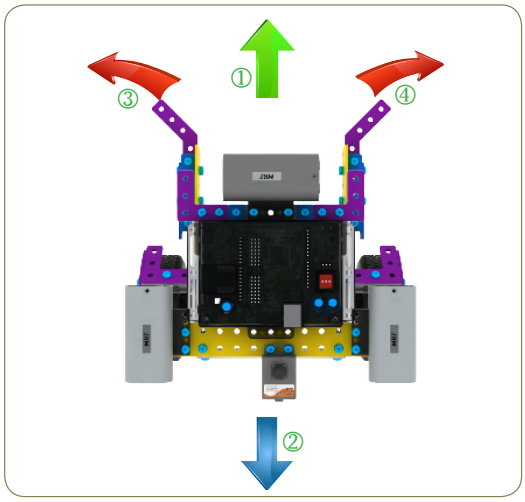
Connecting the mainboard



Please connect in this order:

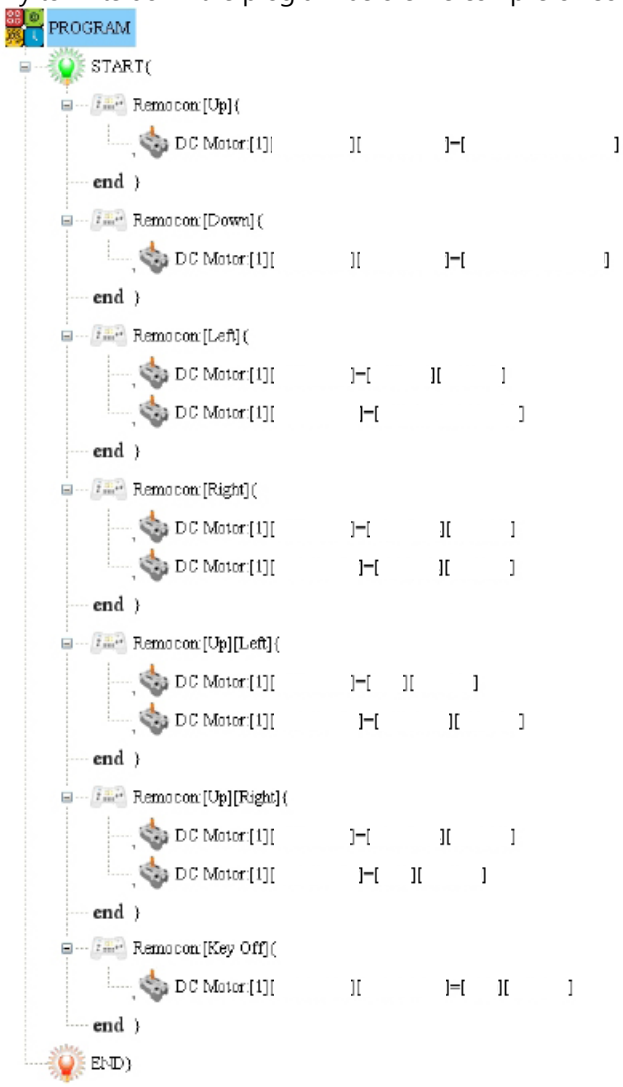
1. Connect left DC motor to L–MOTOR connector1.
2. Connect right DC motor to R–MOTOR connector2.
3. Connect RC Receiver to R/C connector.
4. Connect battery case to Power connector.

Motion Pattern



Learn to compile program in advance

Try to write down the program before we compile on software.



1. Both left and right DC motors go backward, the robot will go forward.
2. Left DC motor goes forward and right DC motor goes backward, the robot will turn left.
3. Left DC motor backward and right DC motor forward, the robot will turn right.
4. Both left and right DC motors go forward, the robot will go backward.
5. Release all buttons, the robot will stop.

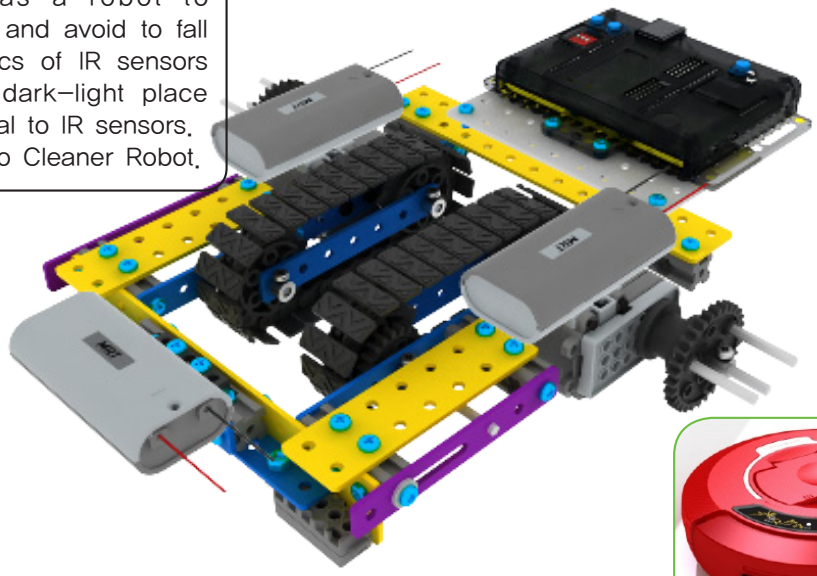
※ Program example : Refer to the back of book.

Program download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download to start".
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

Drop Checker

Drop Checker as a robot to recognize the cliff and avoid to fall down, it with 2 pcs of IR sensors to recognize the dark–light place and send the signal to IR sensors. The same theory to Cleaner Robot.

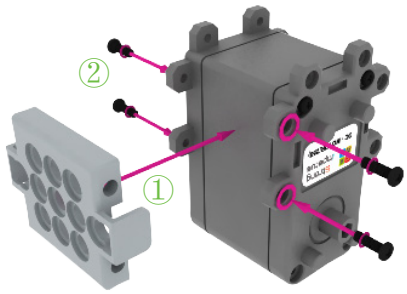


Name	Picture	Quantity
Steel shaft 31mm		4
Steel shaft 70mm		2
Steel shaft 120mm		2
15AL Frame		3
17AL Frame		2
113AL Frame		2
27AL Frame		2
213AL Frame		2
29AL Frame		1
IR Sensor		2

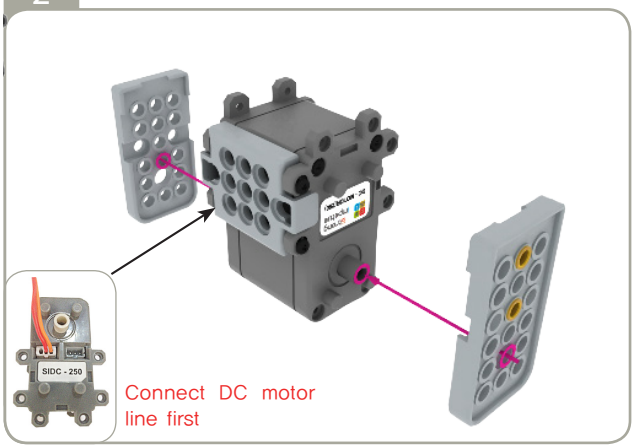
Name	Picture	Quantity
9V Battery Case		1
MRT5–1 Main board		1
DC MOTOR		2
L17AL Frame		2
4–5 Pillar block		1
2–3 Pillar Block		6
Motor Mount		1
Caterpillar		50

Name	Picture	Quantity
Bolt		4
Bolt 8mm		16
Bolt 16mm		18
Bolt 20mm		4
Nut		28
Washer		6
S–Gear		2
Half–Bush		4
Guide Wheel		2
M–Gear		2
L–Gear		2
Sprocket		4
Sleeve pipe		8

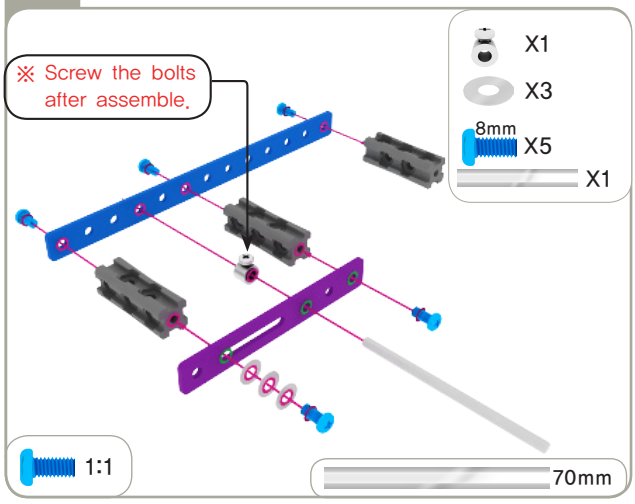
1


②
①

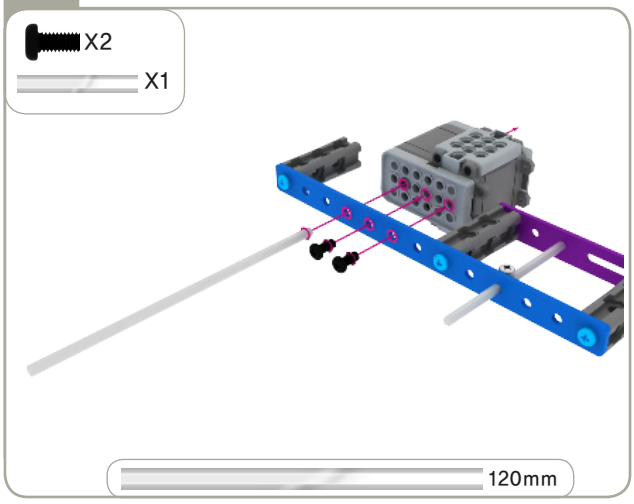
2


SIDC - 250
Connect DC motor line first

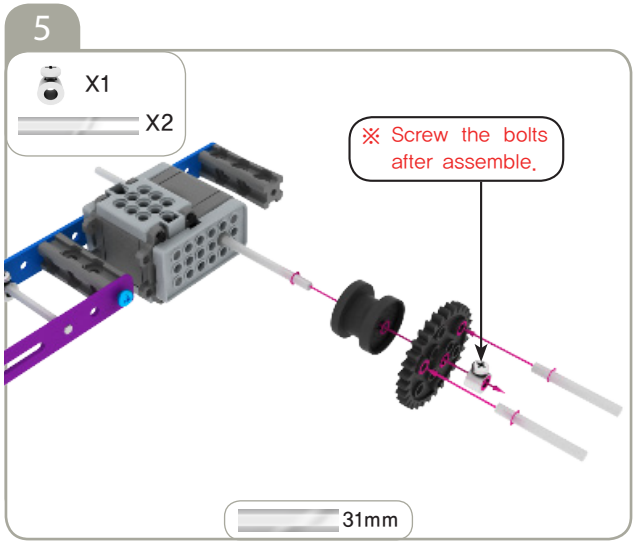
3


※ Screw the bolts after assemble.
X1
X3
8mm X5
X1
1:1
70mm

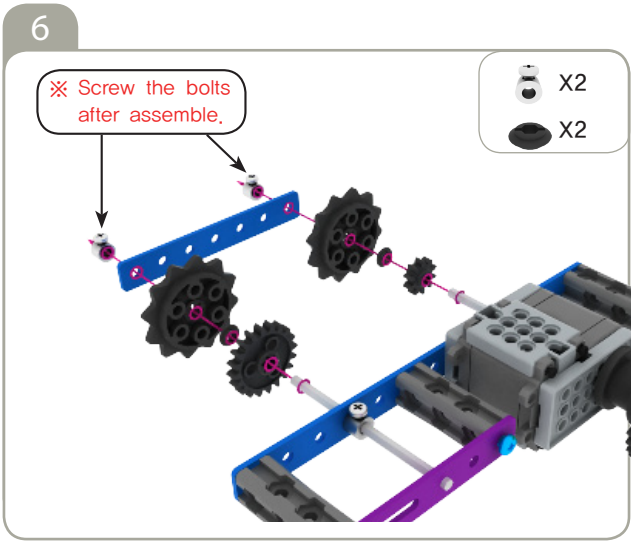
4


X2
X1
120mm

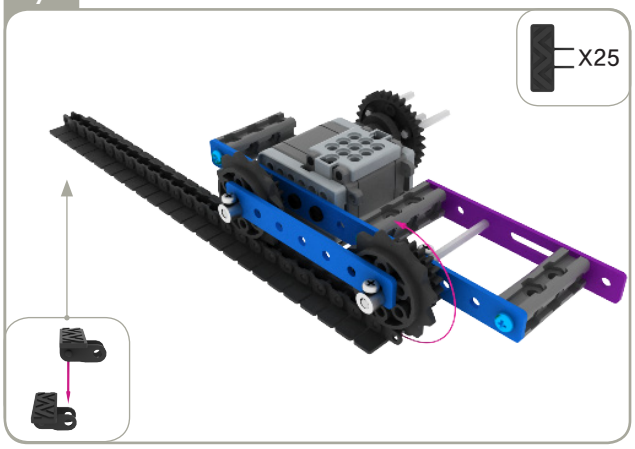
5


X1
X2
※ Screw the bolts after assemble.
31mm

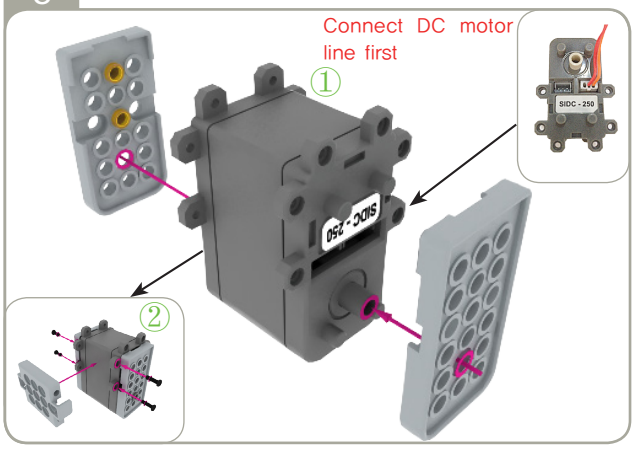
6


※ Screw the bolts after assemble.
X2
X2

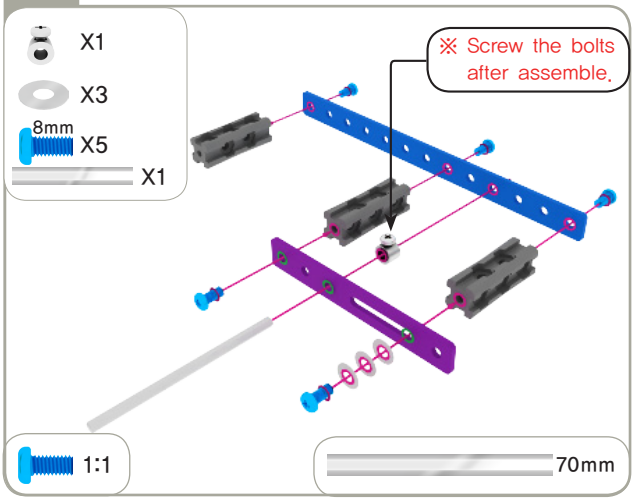
7


X25

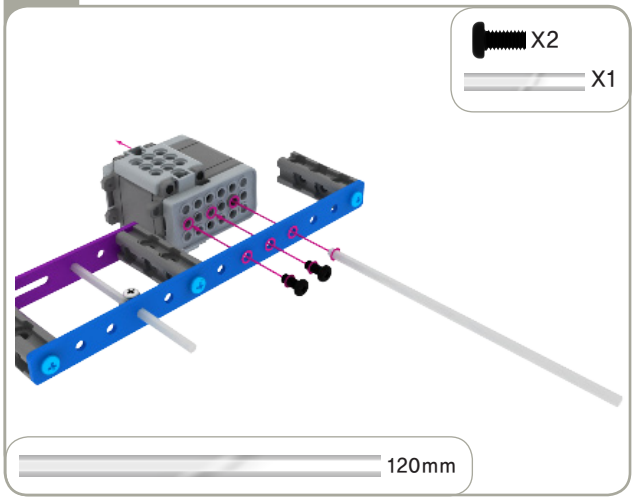
8


Connect DC motor line first
①
②
SIDC - 250

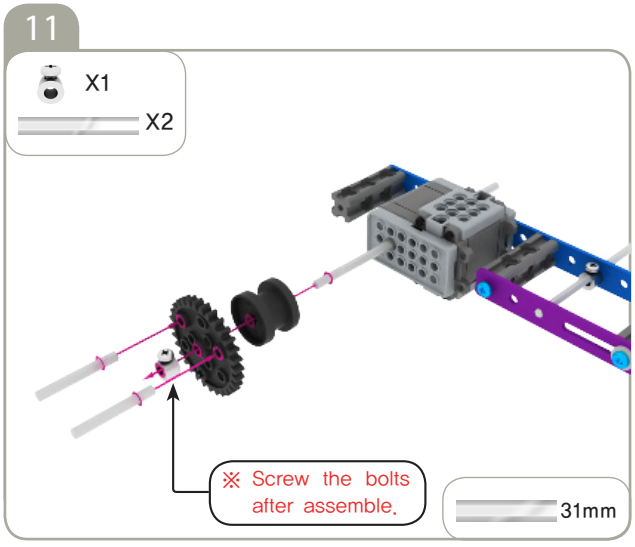
9


X1
X3
8mm
X5
X1
※ Screw the bolts after assemble.
1:1
70mm

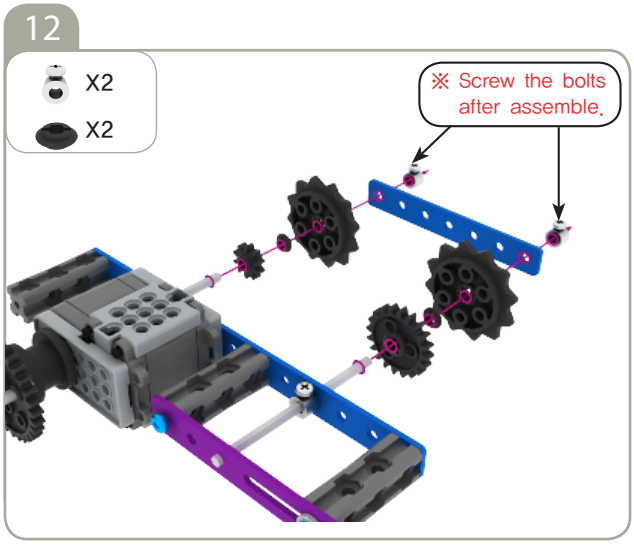
10


X2
X1
120mm

11

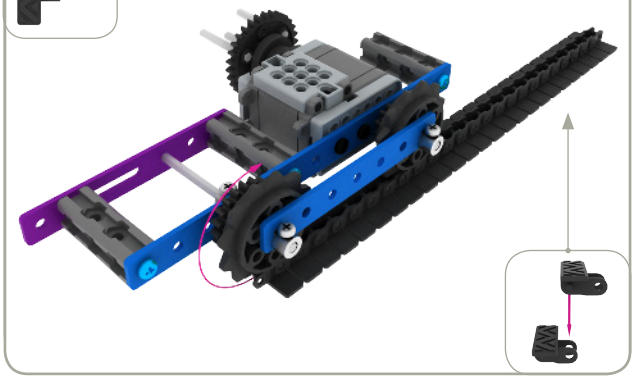

X1
X2
※ Screw the bolts after assemble.
31mm

12


X2
X2
※ Screw the bolts after assemble.

13

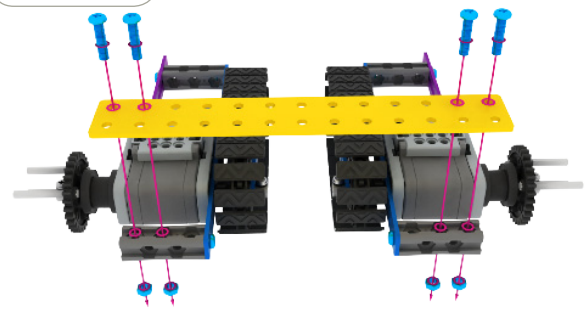
X25



14

16mm X4

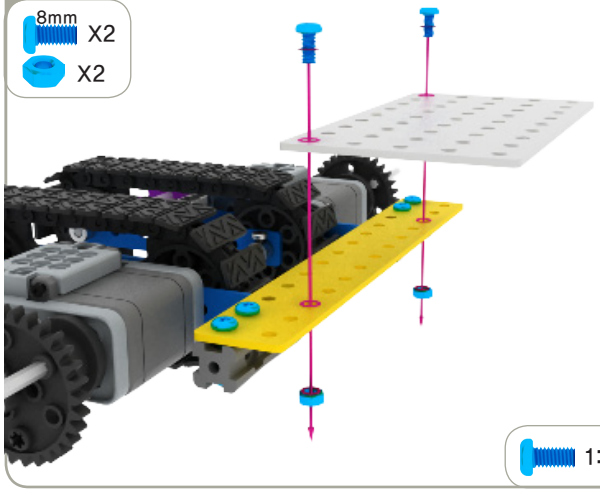
X4



15

8mm X2

X2

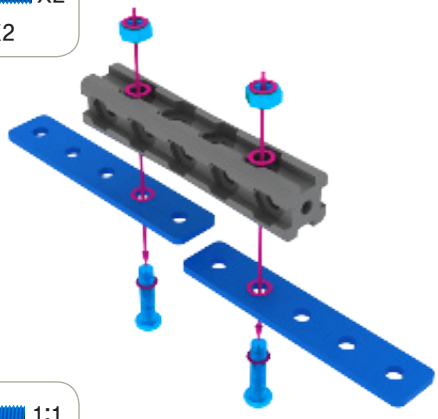


1:1

16

16mm X2

X2

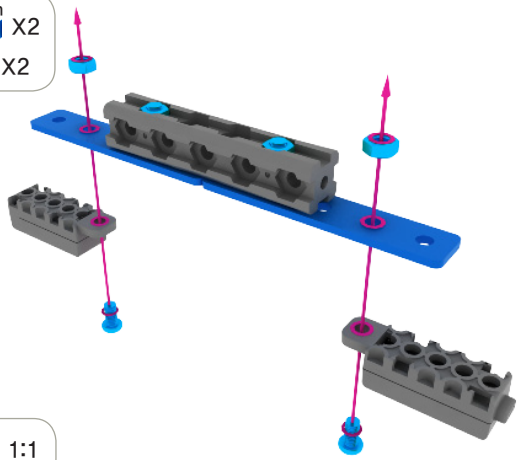


1:1

17 Connect IR sensor

8mm X2

X2

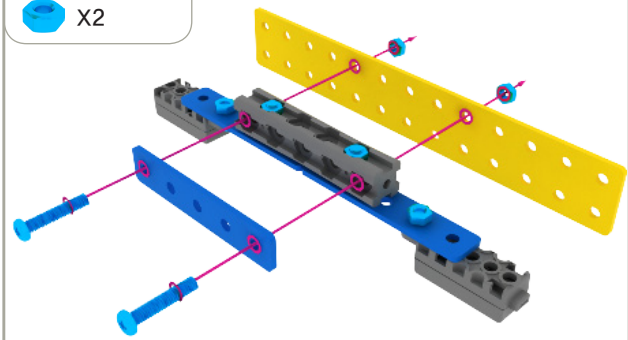


1:1

18

20mm X2

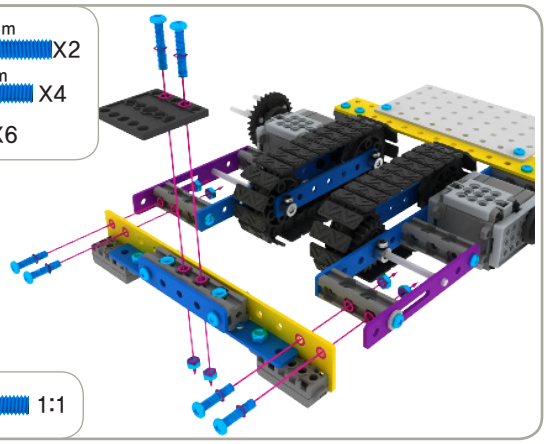
X2



1:1

19

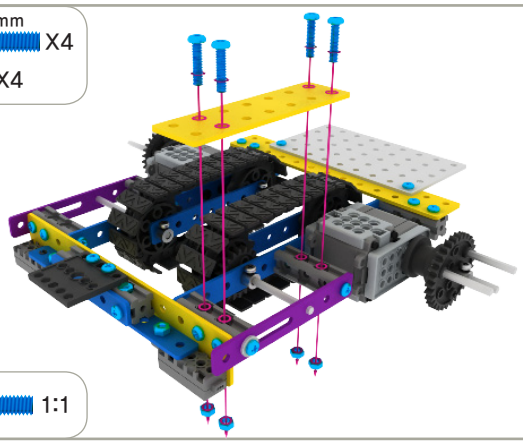
20mm X2
16mm X4
X6



1:1

20

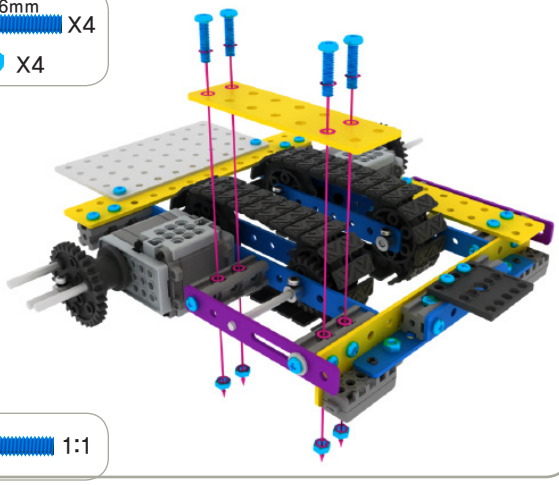
16mm X4
X4



1:1

21

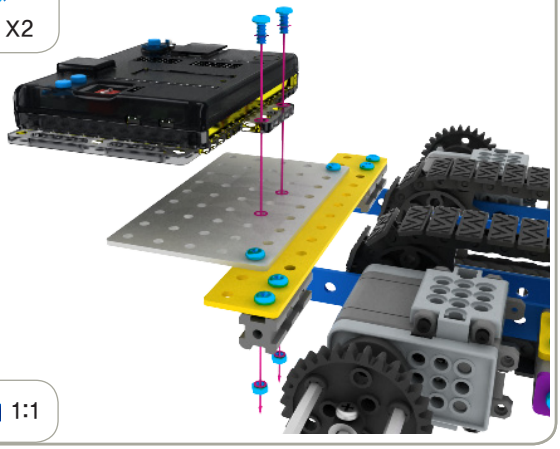
16mm X4
X4



1:1

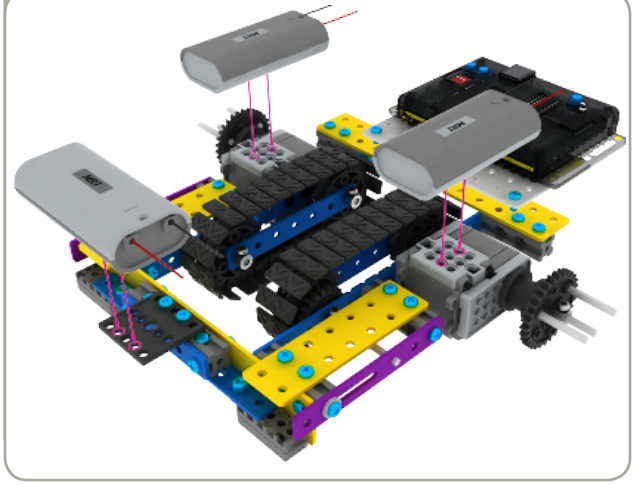
22

8mm X2
X2

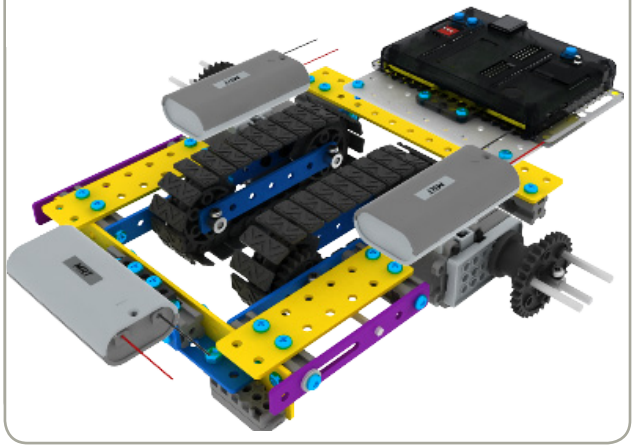


1:1

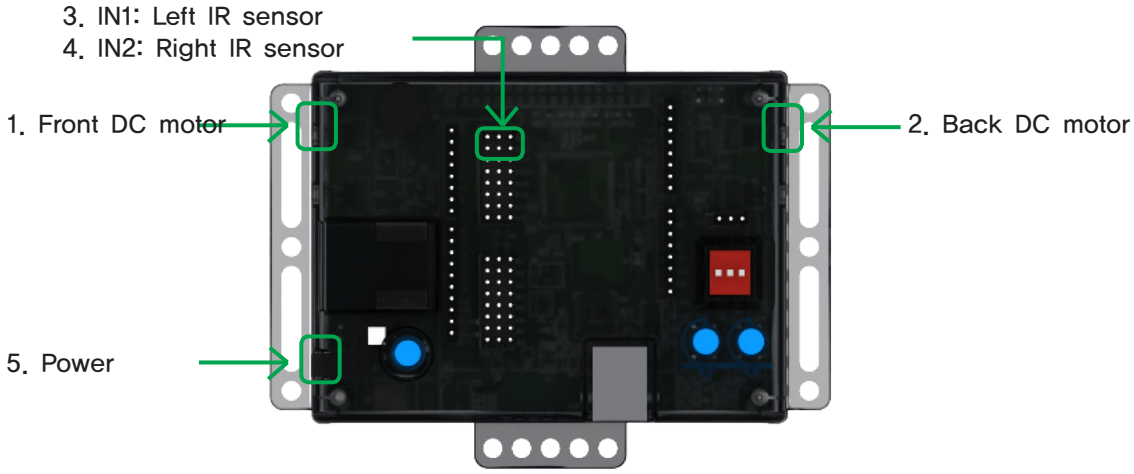
23



Complete



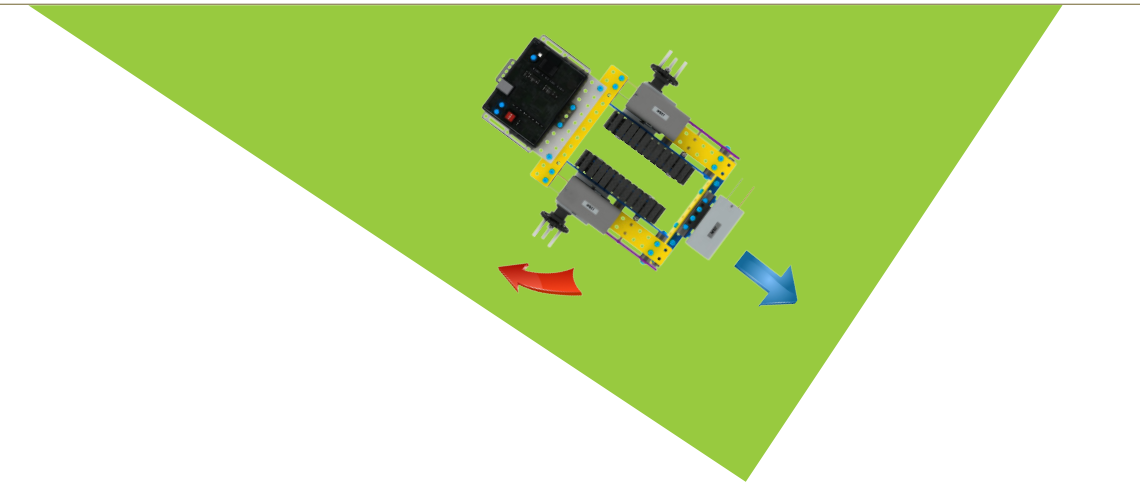
Connecting the mainboard



Please connect in this order:

1. Connect front DC motor to L–MOTOR connector1.
2. Connect back DC motor to R–MOTOR connector 1.
3. Connect left IR sensor to INPUT1 connector.
4. Connect right IR sensor to INPUT2 connector.
5. Connect battery case to Power connector.

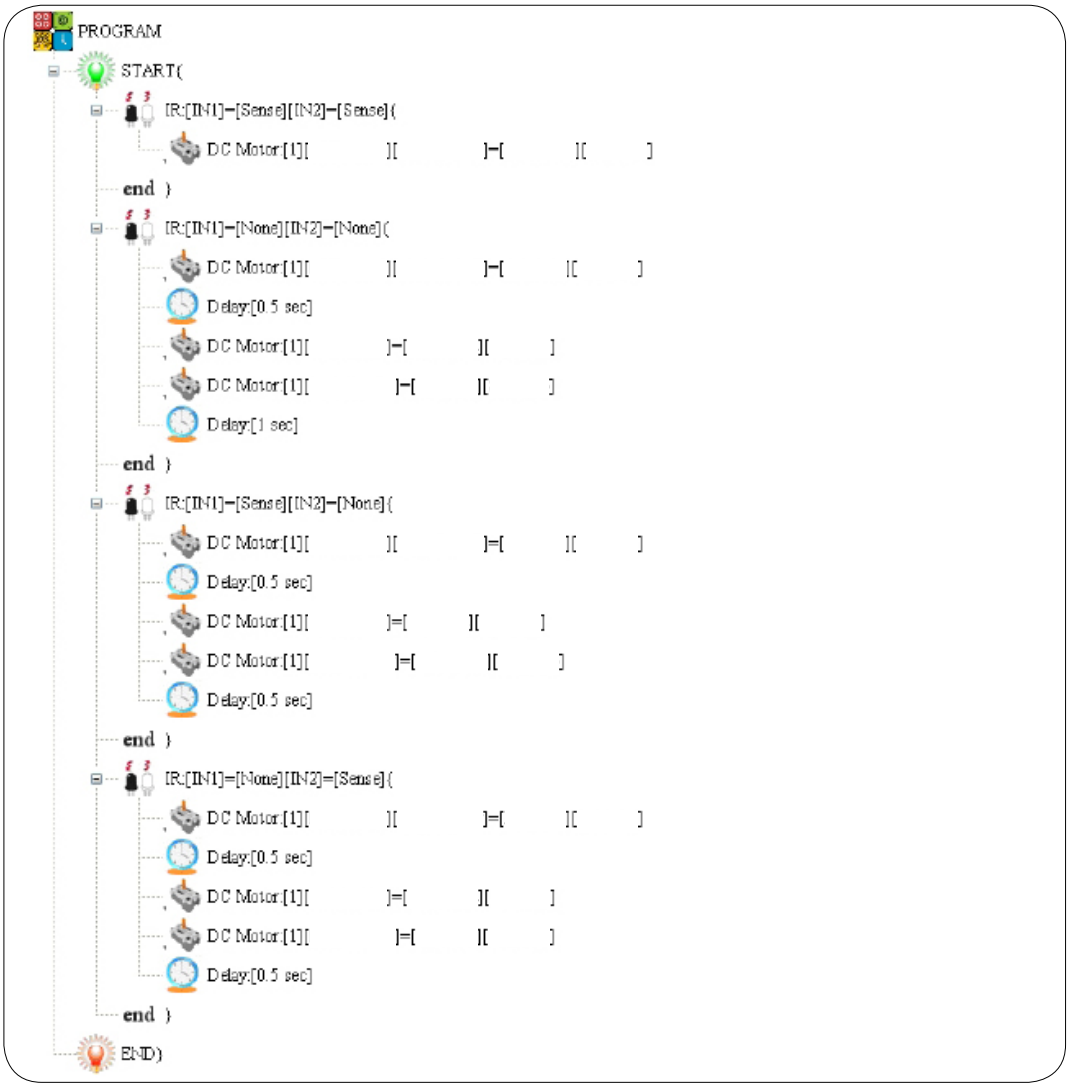
Motion Pattern



※ Robot will turn left or right , or turn 180 degrees when recognize the edge.

Learn to compile program in advance

Try to write down the program before we compile on software.



1. Recognize left IR sensor, robot will go backward and turn right.
2. Recognize right IR sensor, robot go backward and turn left.
3. Recognize both IR sensors, robot go backward and turn 180 degrees.
4. Regonize nothing, robot goes forward.

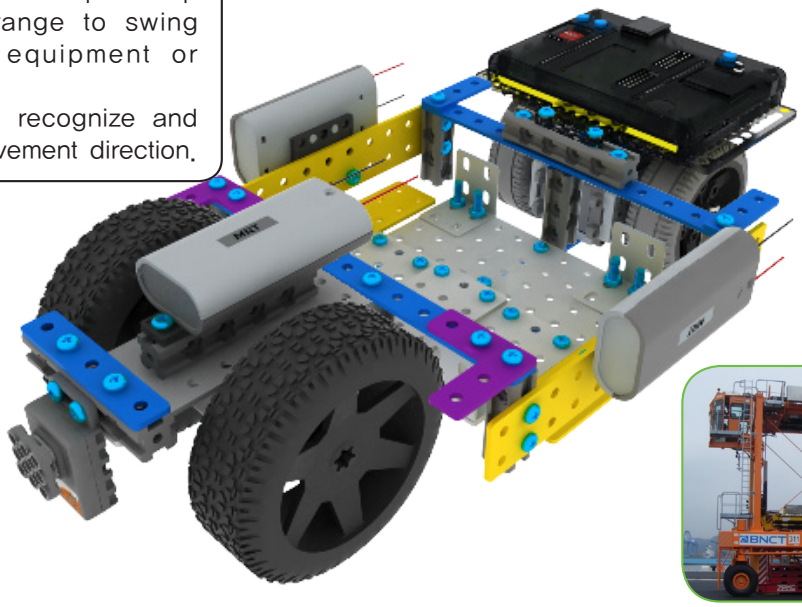
※ Program example : Refer to the back of book.

Program download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download to start".
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

SHUTTLE CARRIER

Shuttle Carrier as a transport ship within a certain range to swing transport heavy equipment or human.
Two touch sensors recognize and aboard the anti–movement direction.



Name	Picture	Quantity
Steel shaft 120mm		2
13AL Frame		7
15AL Frame		3
17AL Frame		2
113AL Frame		2
27AL Frame		2
213AL Frame		2
39AL Frame		2
59AL Frame		2

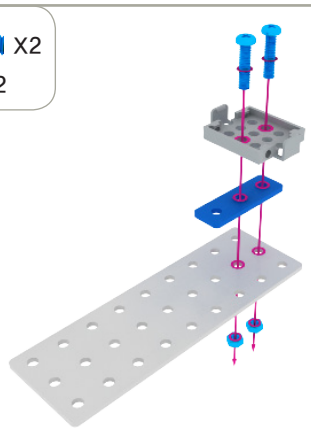
Name	Picture	Quantity
9V Battery Case		1
MRT5–1 Main board		1
DC MOTOR		2
AL Frame90		2
4–5 Pillar block		3
2–3 Pillar Block		8
Motor Mount		2

Name	Picture	Quantity
Bolt 8mm		28
Bolt 16mm		30
Bolt 20mm		3
Nut		51
Guide Wheel		2
M–Gear		2
Sleeve pipe		4
Big Wheel1		2
Big Wheel2		2
Touch Sensor		2
D90 S–Bracket		4
9 Hole Motor Mount		1

1

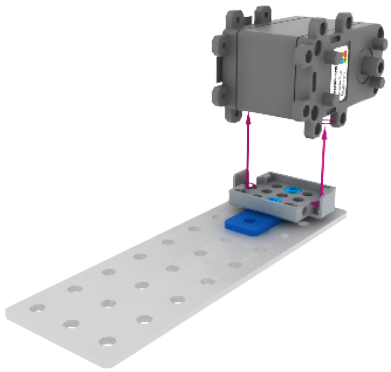
16mm X2

X2

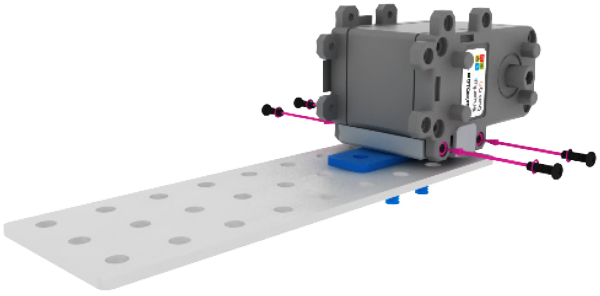


1:1

2

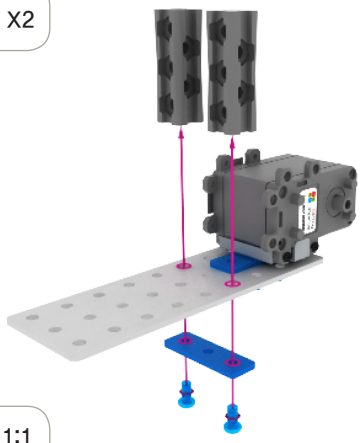


3



4

8mm X2

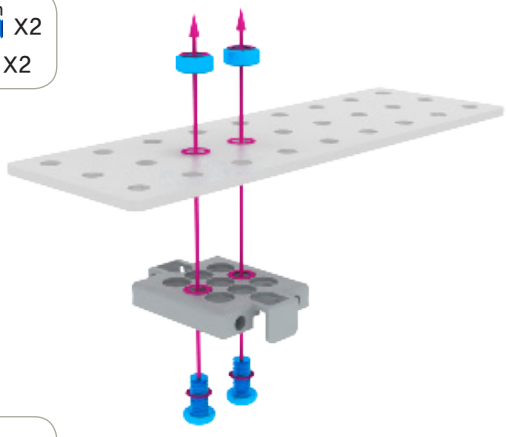


1:1

5

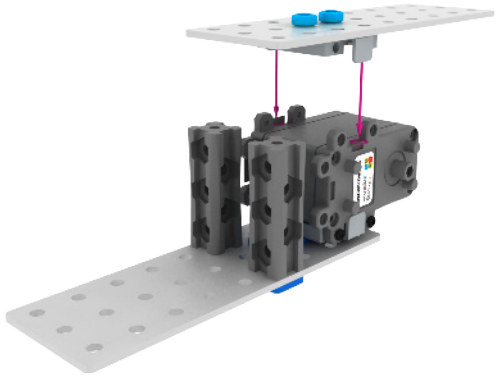
8mm X2

X2

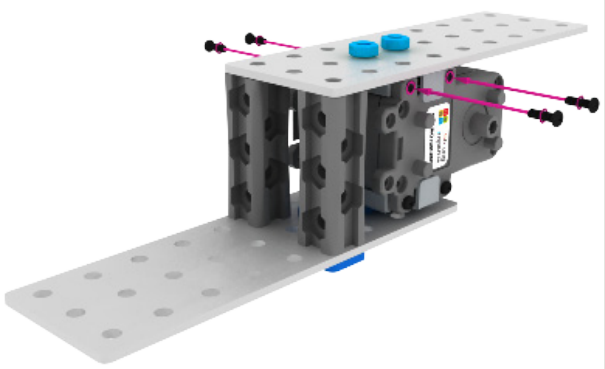


1:1

6



7



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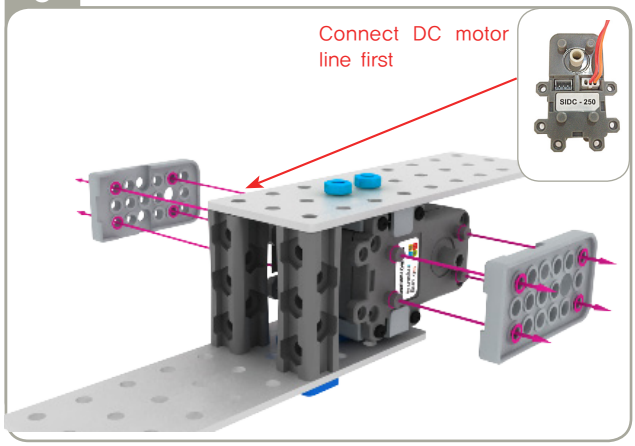
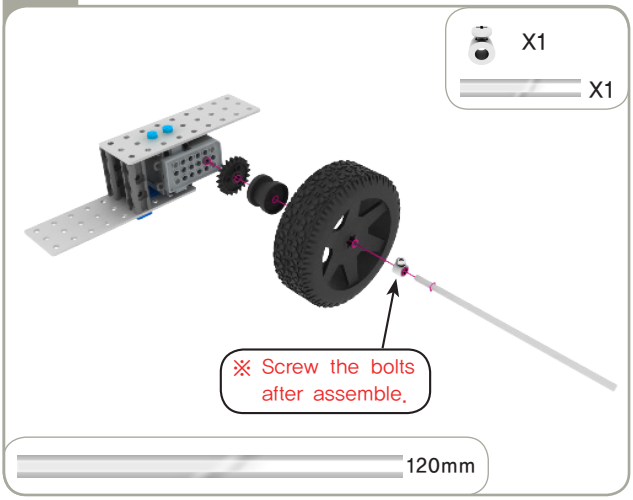
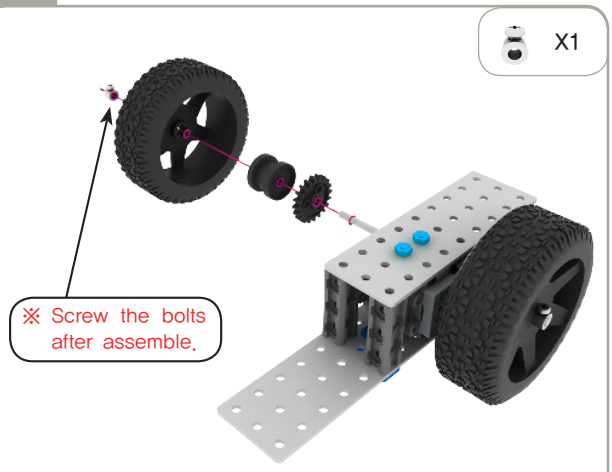

Connect DC motor
line first
SIDC - 250

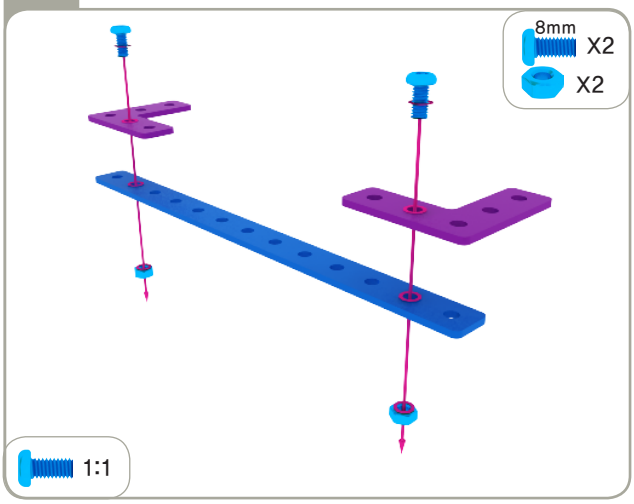
9


X1
X1
※ Screw the bolts
after assemble.
120mm

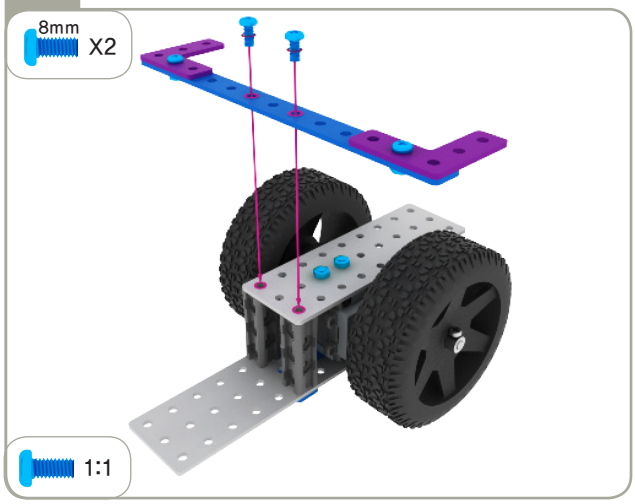
10


X1
※ Screw the bolts
after assemble.

11


8mm
X2
X2
1:1

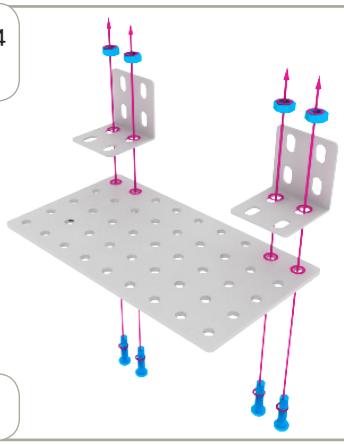
12


8mm
X2
1:1

13

16mm X4

X4



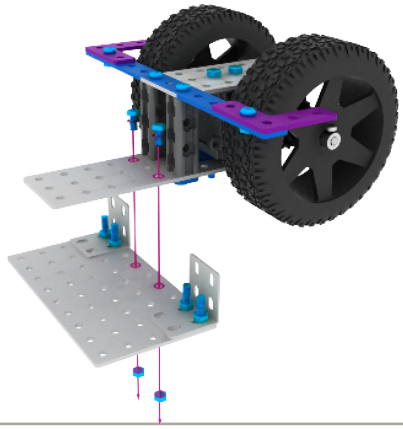
X2

1:1

14

8mm X2

X2

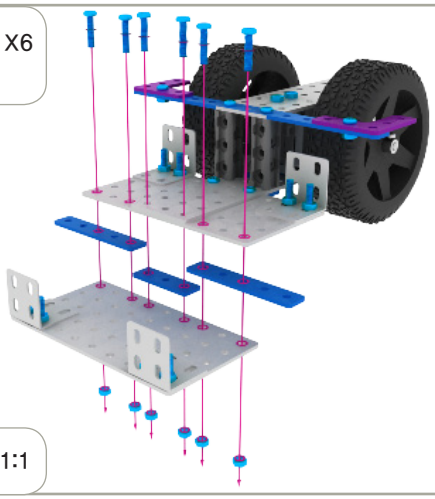


1:1

15

16mm X6

X6

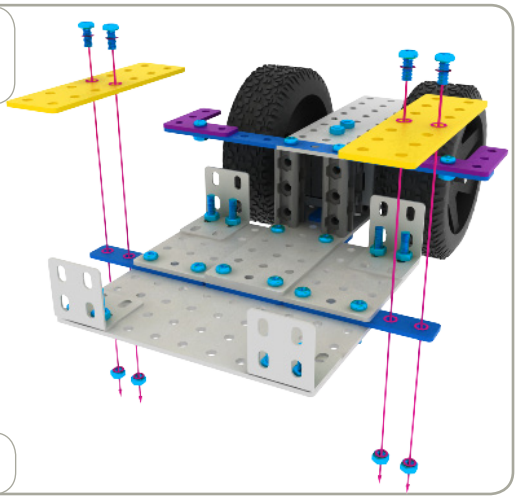


1:1

16

8mm X4

X4

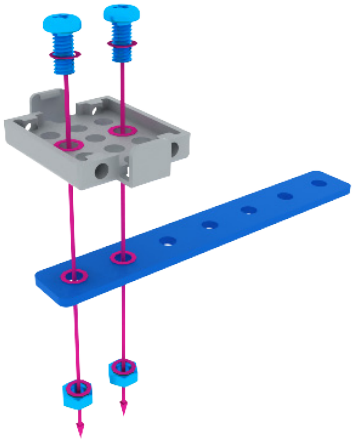


1:1

17

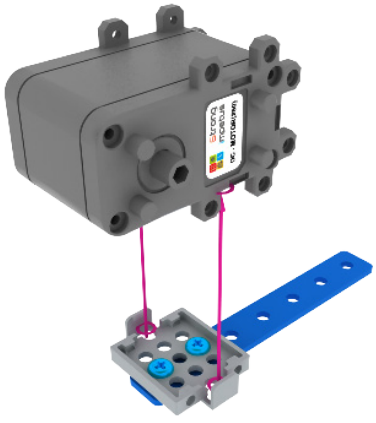
8mm X2

X2

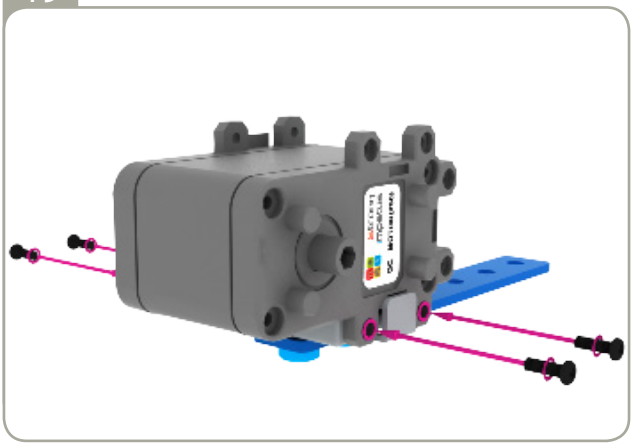


1:1

18

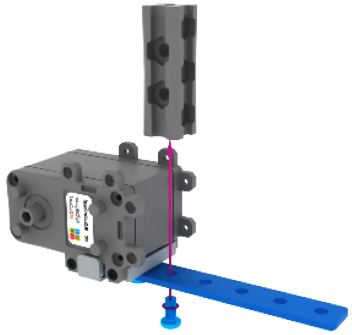


19



20

8mm X1



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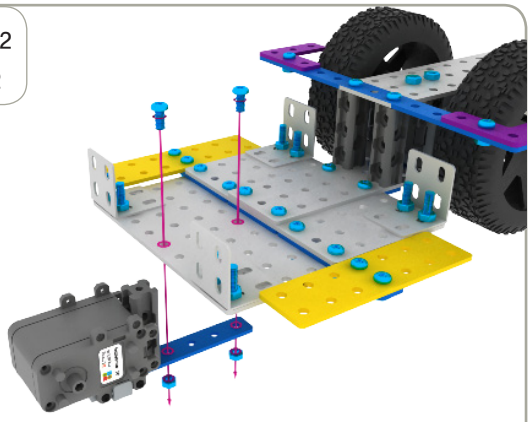
21

8mm X2

X2



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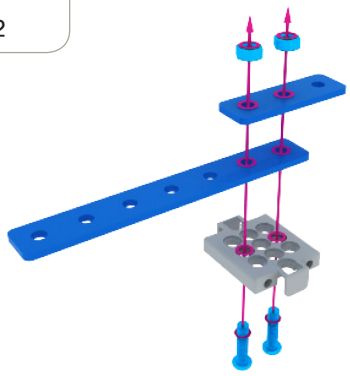
22

16mm X2

X2



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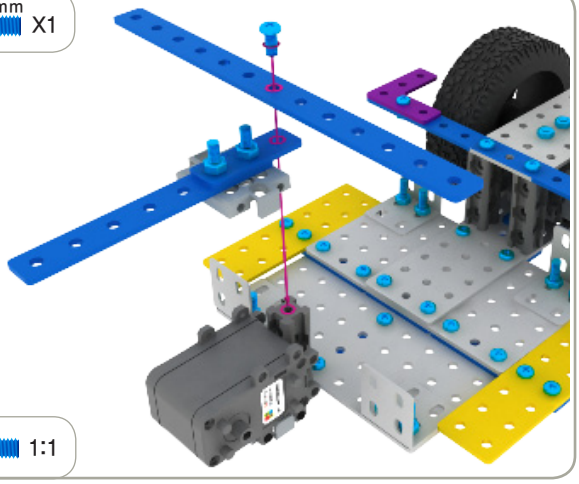
23

8mm X1



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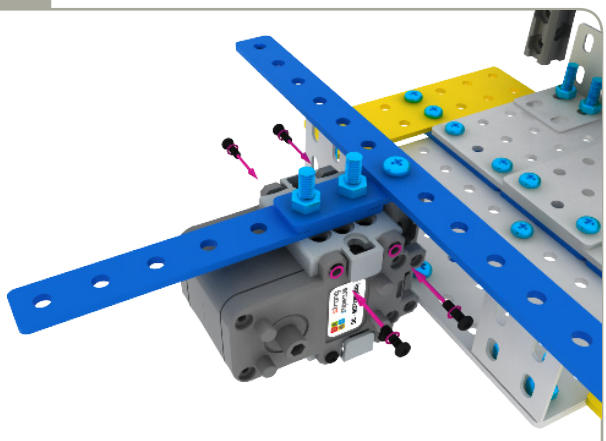

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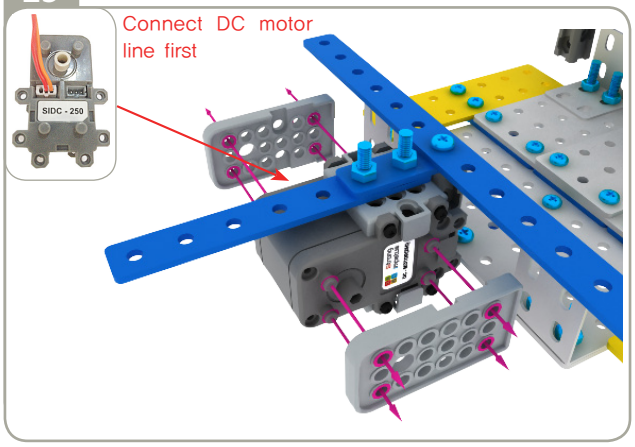

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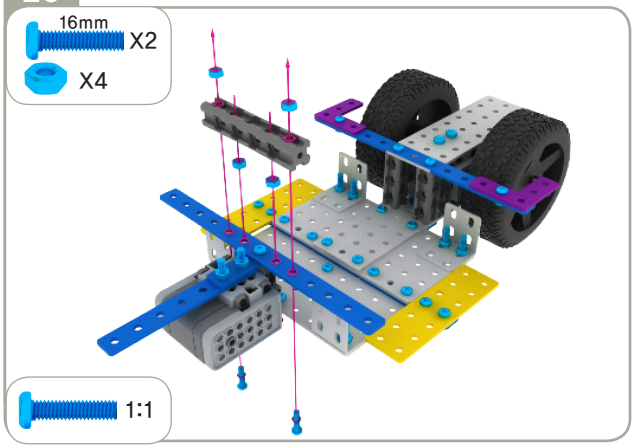

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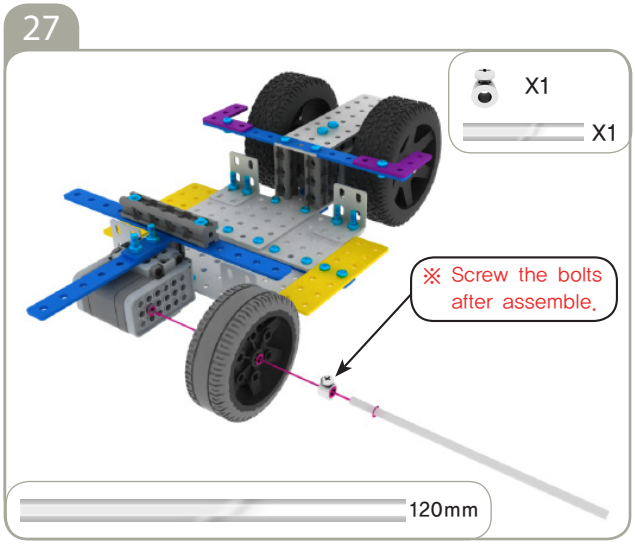

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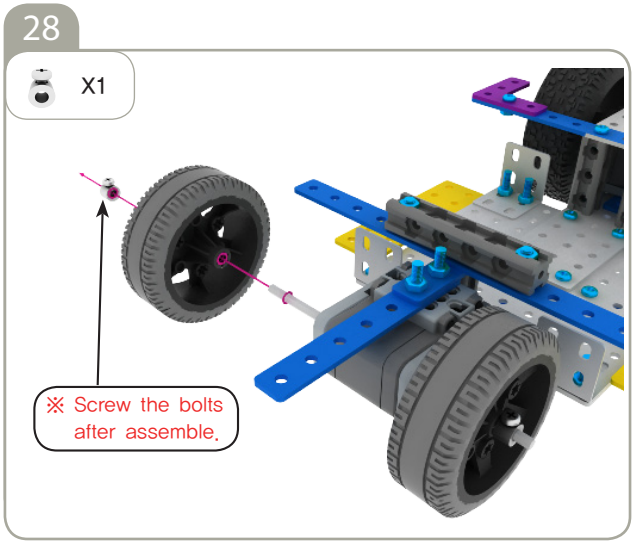

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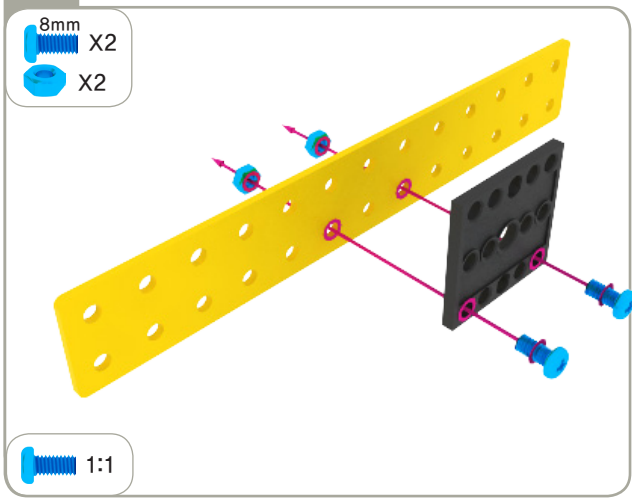

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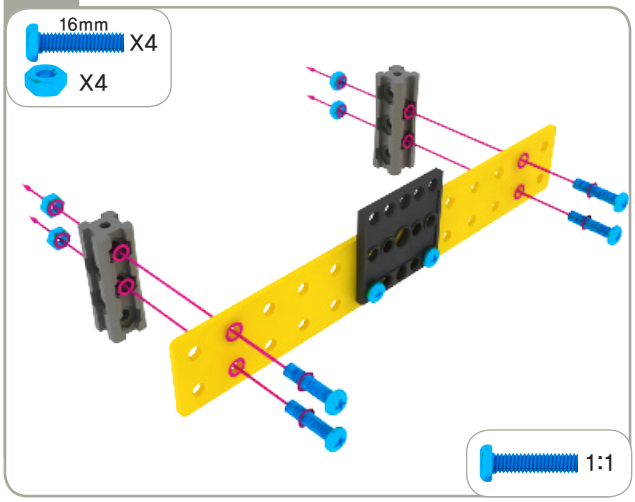
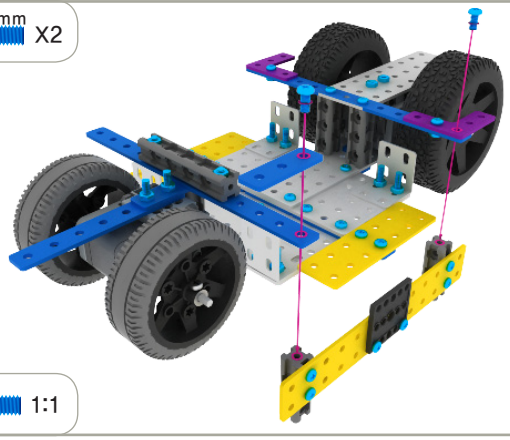


31

8mm X2

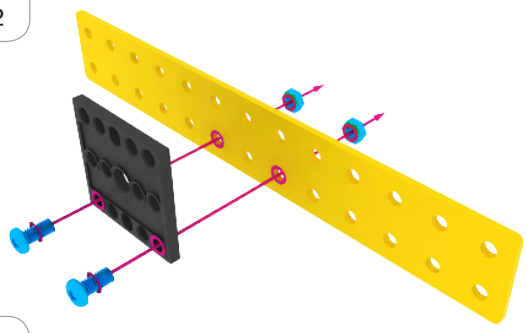


1:1

32

8mm X2

X2



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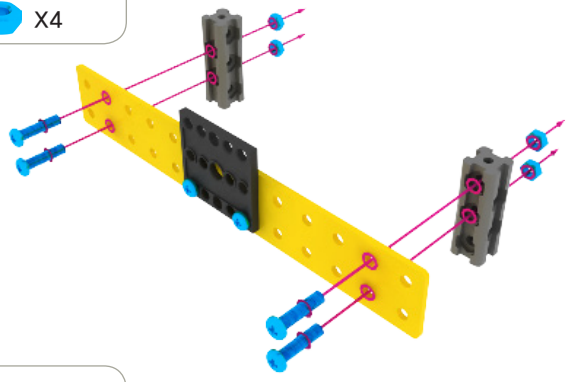
33

16mm X4

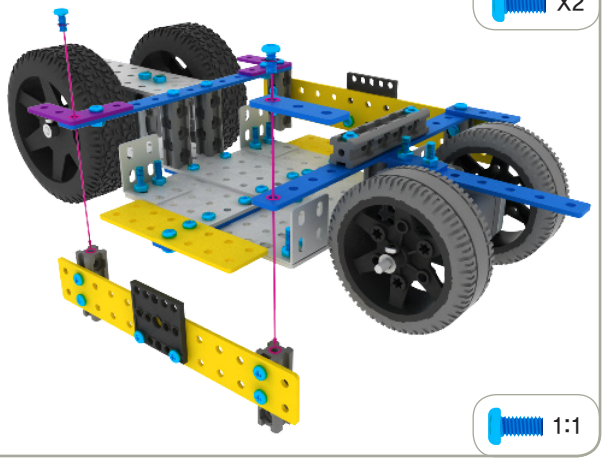
X4



1:1

34

8mm X2

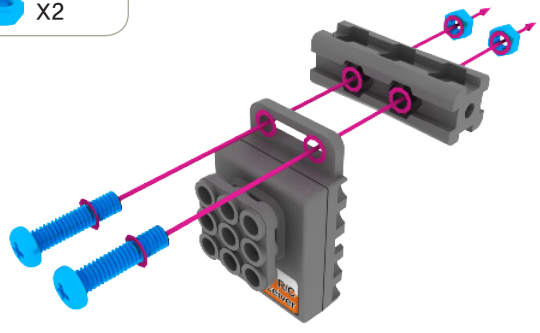


1:1

35

16mm X2

X2

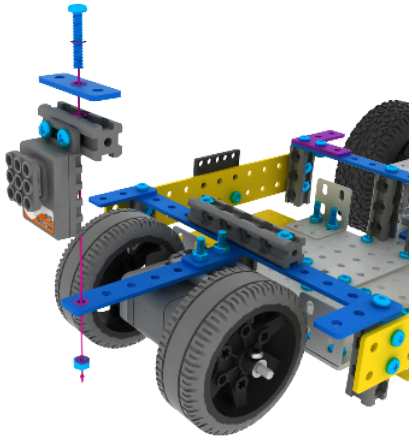


1:1

36

20mm X1

X1



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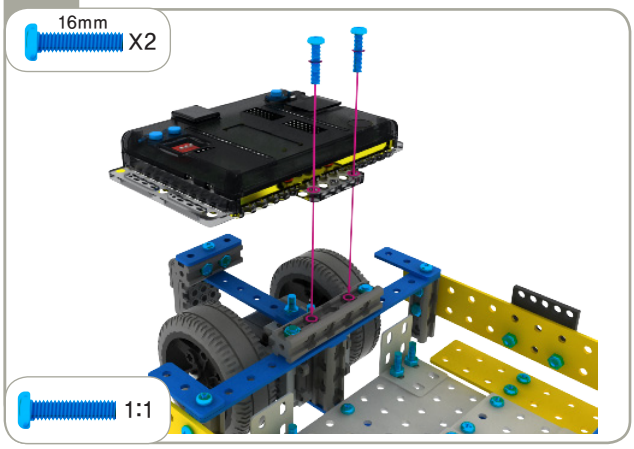
37



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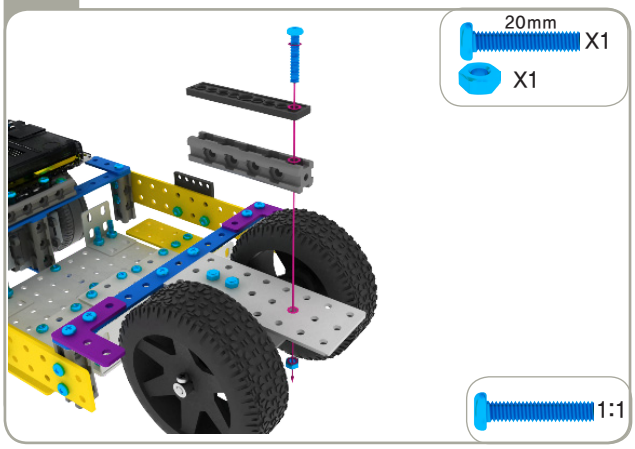

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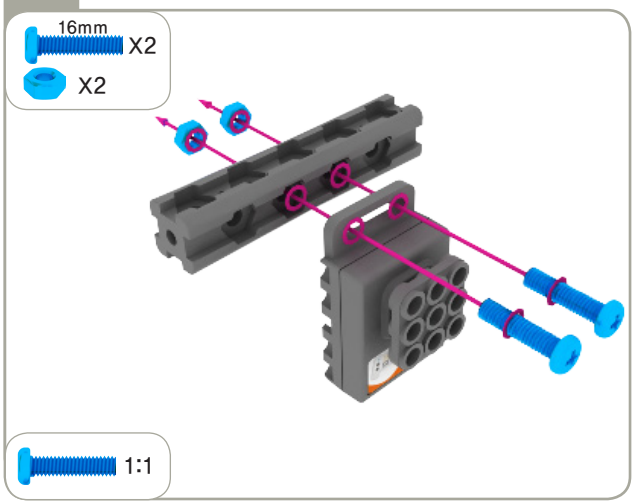

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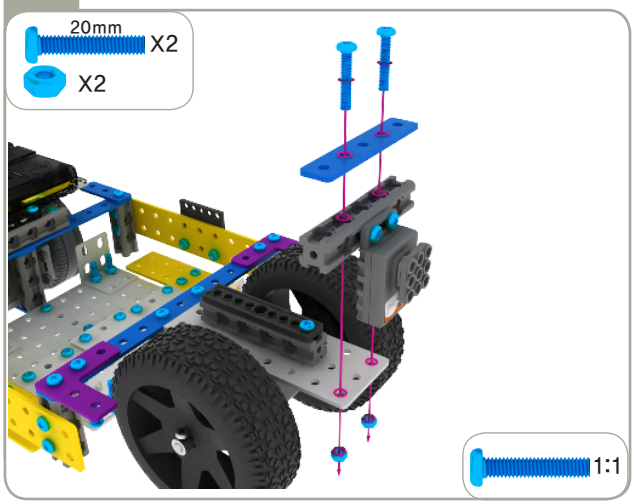

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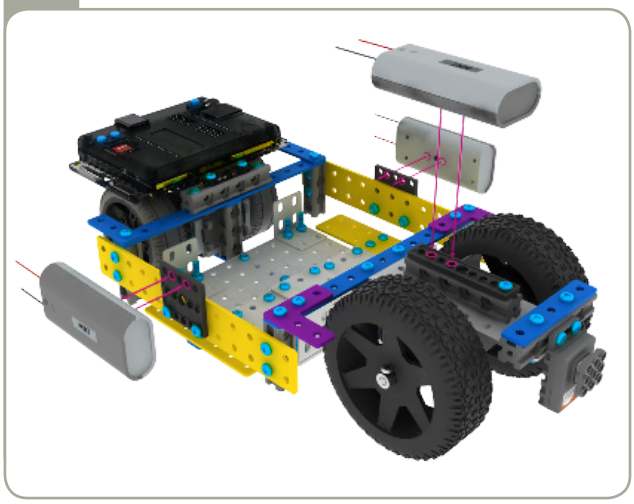
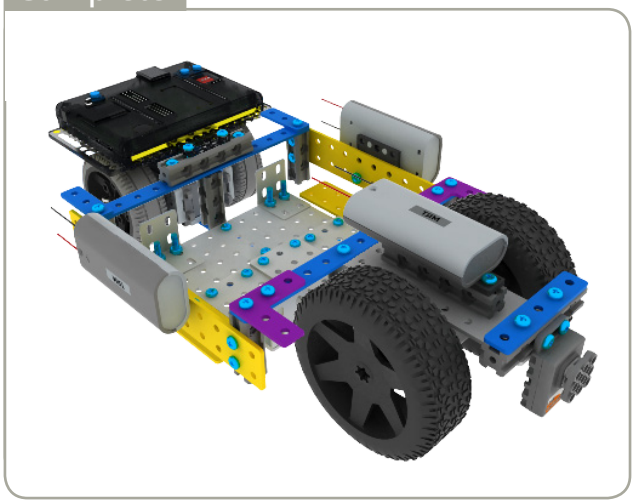
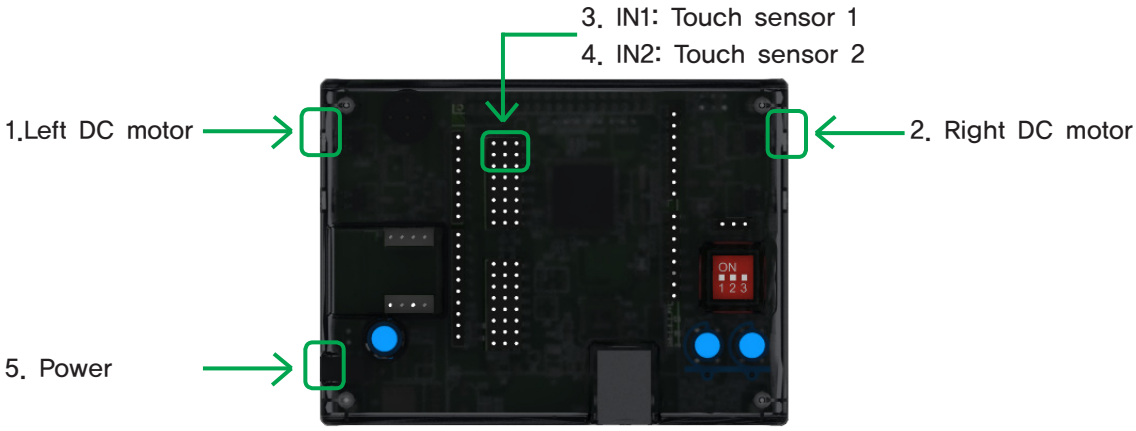


Complete



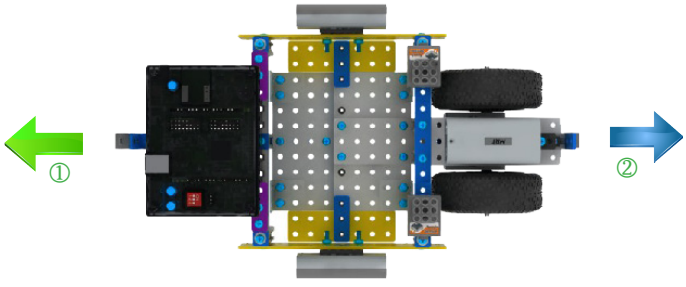
Connecting the mainboard



Please connect in this order:

1. Connect left DC motor to L–MOTOR connector.
2. Connect right DC motor to R–MOTOR connector.
3. Connect Touch sensor1 to INPUT1 connector.
4. Connect Touch sensor2 to INPUT2 connector.
5. Connect battery case to Power connector.

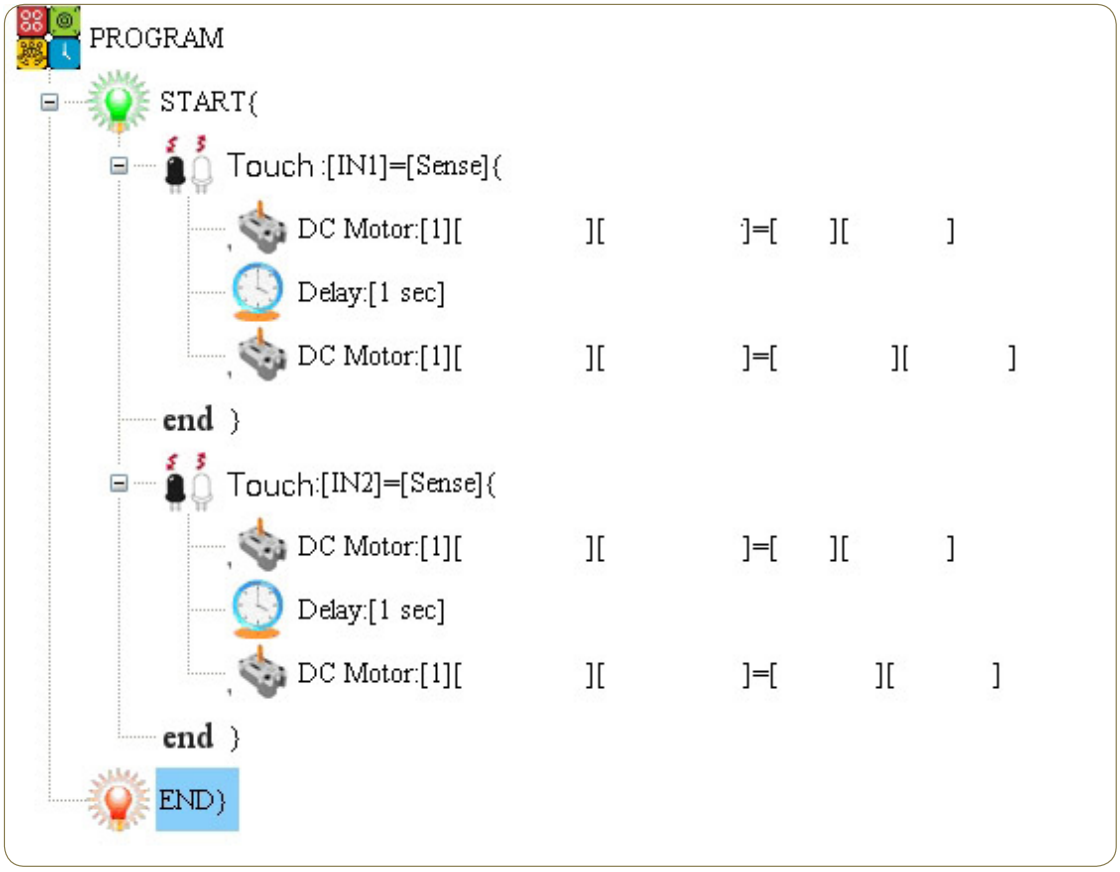
Motion Pattern



1. Recognize Touch sensor1, robot will move in opposite direction.
2. Recognize Touch sensor 2, robot will move in opposite direction again.

Learn to compile program in advance

※ Try to write down the program before we compile on software.



1. Recognize Touch sensor1, robot will move in opposite direction.
2. Recognize Touch sensor 2, robot will move in opposite direction again.

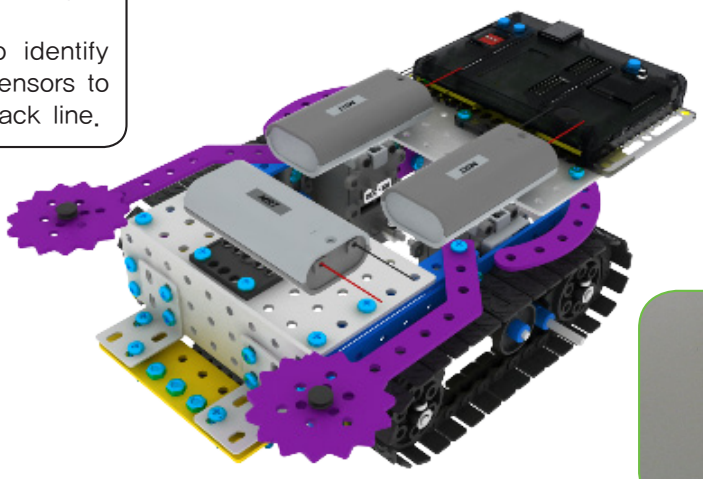
※ Movement and transport ship are similar theory.

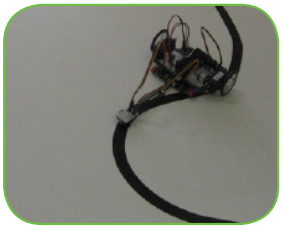
Program download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download" to start.
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

TRACING TANK

Tracing Tank walks along the black line with 3 pcs of IR sensors.
Using reflection to identify the infrared light sensors to walks along the black line.





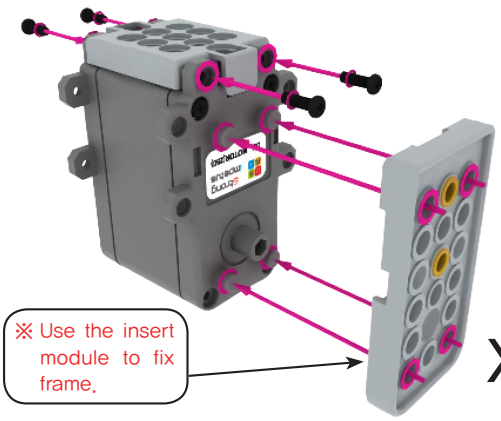
Name	Picture	Quantity
Steel shaft 44mm		4
Steel shaft 70mm		2
Steel shaft 95mm		2
17AL Frame		2
113AL Frame		2
27AL Frame		1
213AL Frame		2
39AL Frame		2
59AL Frame		2
2–3 Pillar Block		6
Motor Mount		1
Caterpillar		66
IR Sensor		3

Name	Picture	Quantity
9V Battery Case		1
MRT5–1 Main board		1
DC MOTOR		2
AL Frame 90		4
AL Sprocket		2
AL Round Block		2
AL Frame 135		2
M–Gear		2

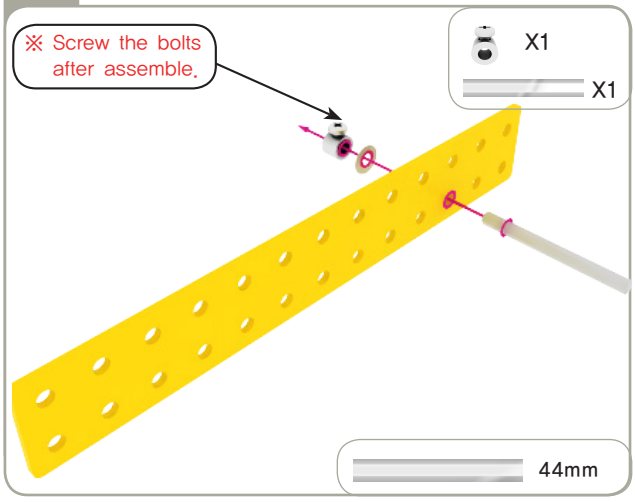
Name	Picture	Quantity
Bolt		4
Bolt 8mm		19
Bolt 16mm		16
Bolt 20mm		12
Nut		41
ABS Connecting shaft		2
B–Bush		10
Washer		6
S–Gear		2
Half–Bush		4
Guide Wheel		2
L–Gear		2
Sprocket		4
Sleeve pipe		10
D90 S–Bracket		2

1

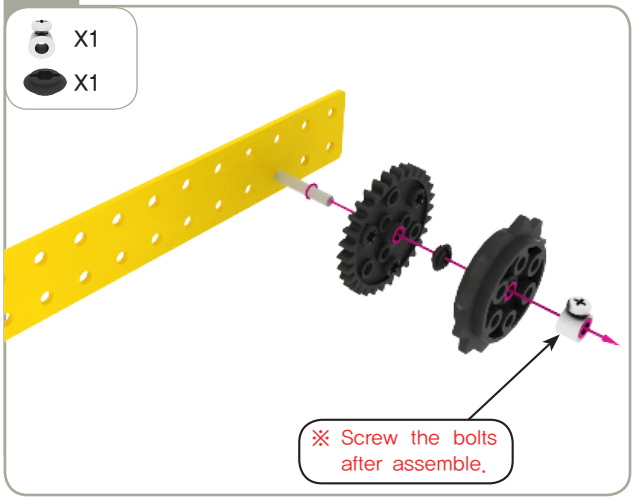
2


※ Use the insert module to fix frame.
X2

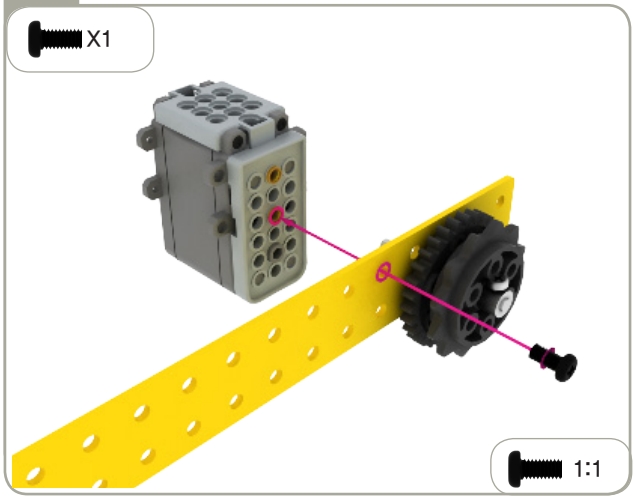
3


※ Screw the bolts after assemble.
X1
X1
44mm

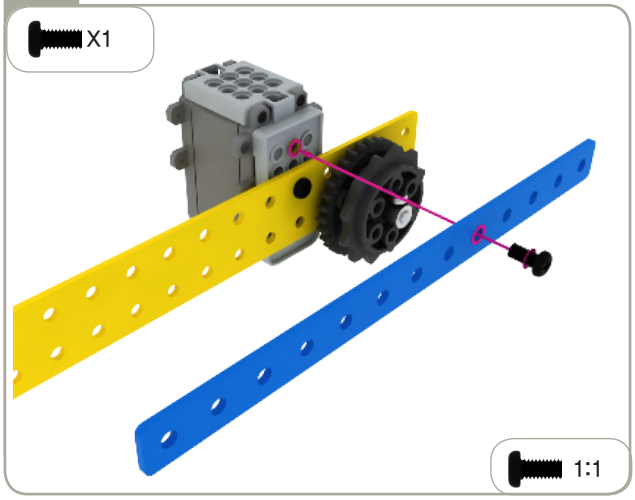
4


X1
X1
※ Screw the bolts after assemble.

5


X1
1:1

6

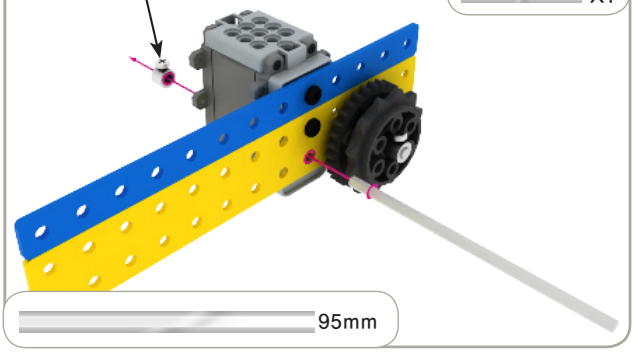

X1
1:1

7

※ Screw the bolts after assemble.

X1

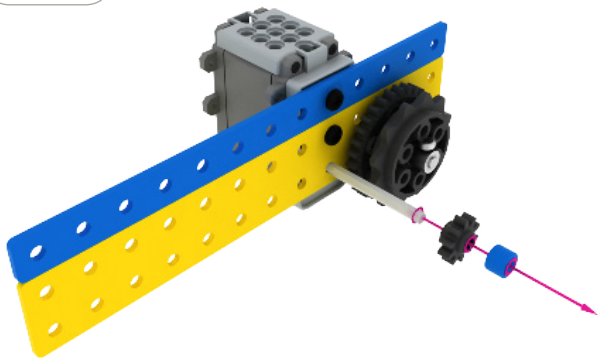
X1



95mm

8

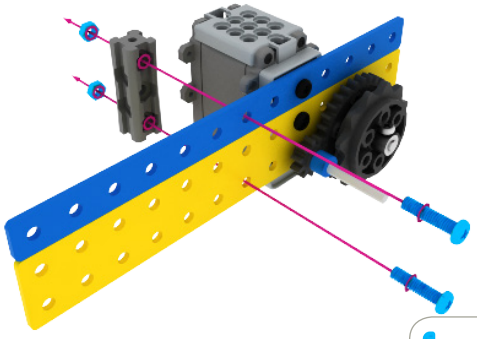
X1



9

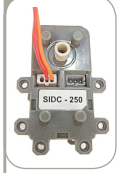
16mm X2

X2



1:1

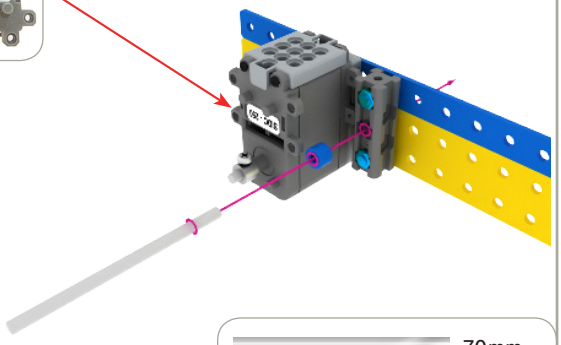
10



Connect DC motor line first

X1

X1

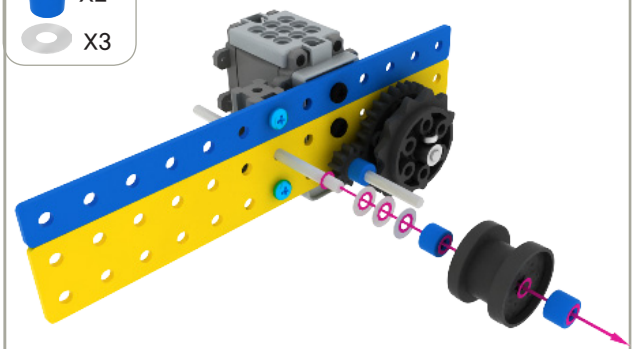


70mm

11

X2

X3

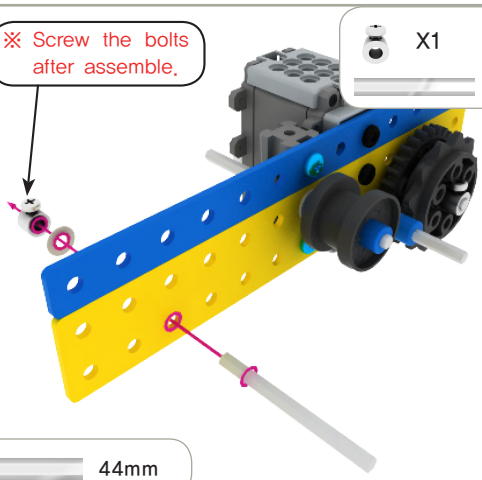


12

※ Screw the bolts after assemble.

X1

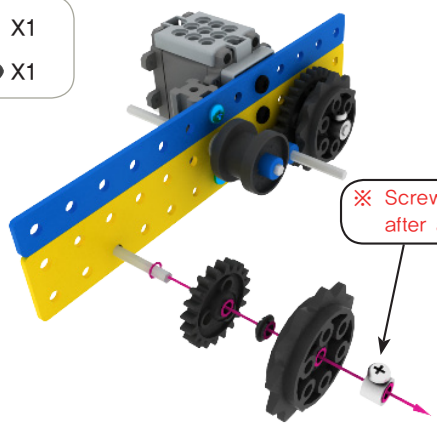
X1



44mm

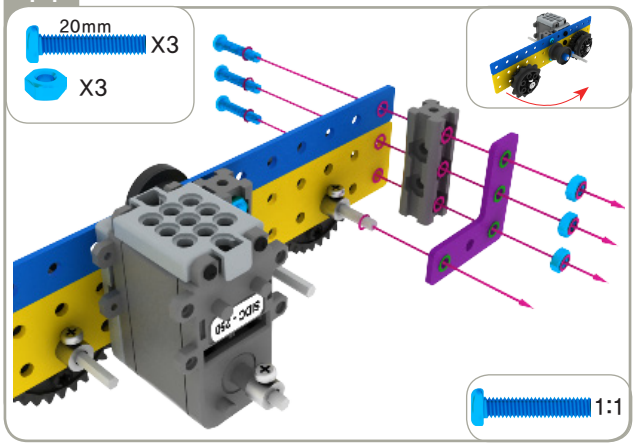
13

X1
X1



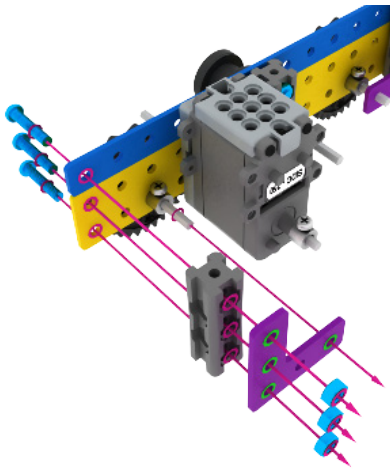
14

20mm X3
X3



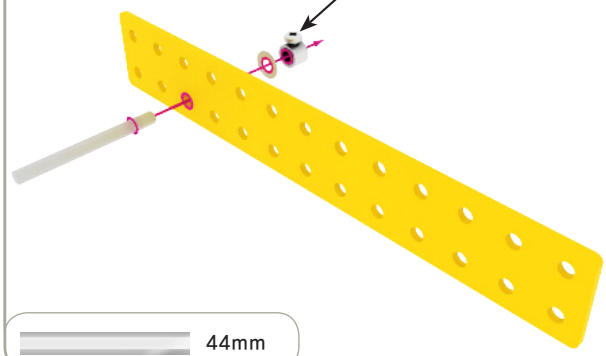
15

20mm X3
X3



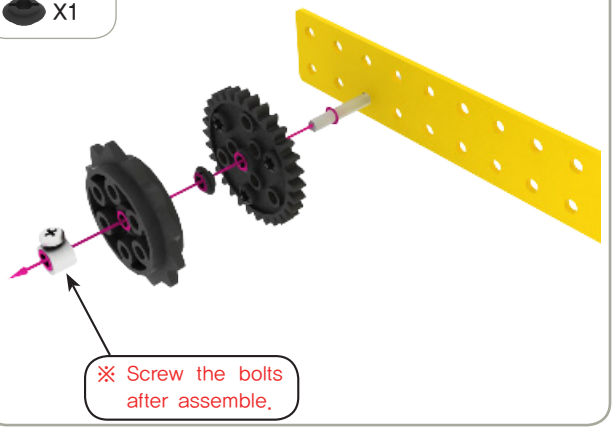
16

X1
X1



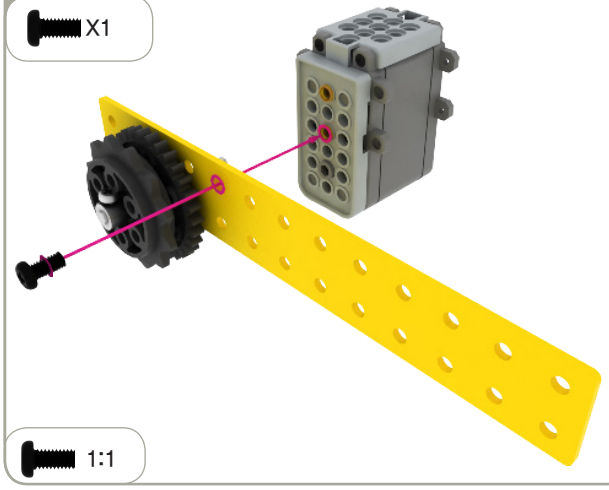
17

X1
X1



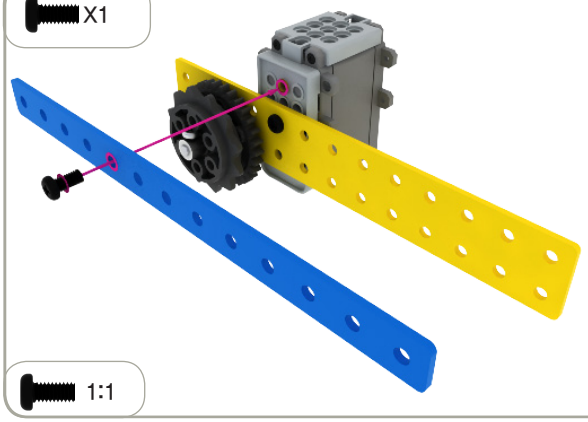
18

X1



19

X1



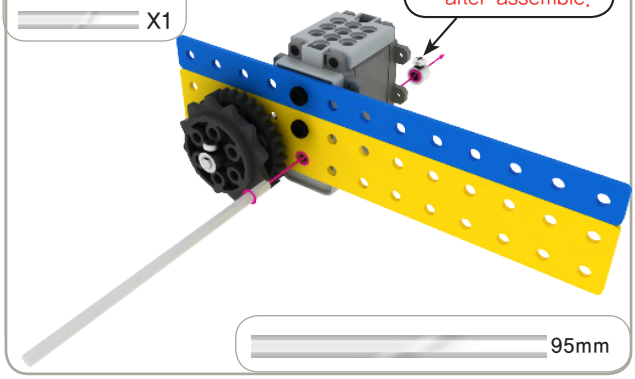
1:1

20

X1

X1

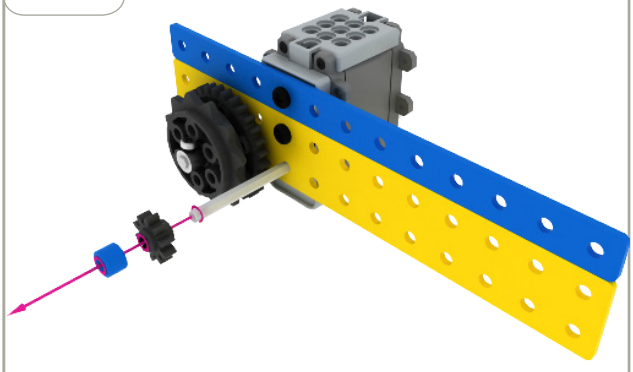
※ Screw the bolts after assemble.



95mm

21

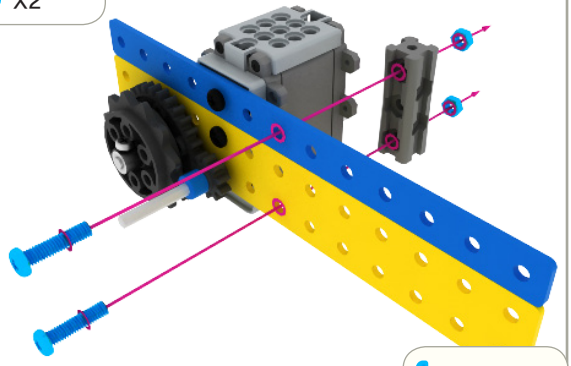
X1



22

16mm X2

X2



1:1

23

X1

X1

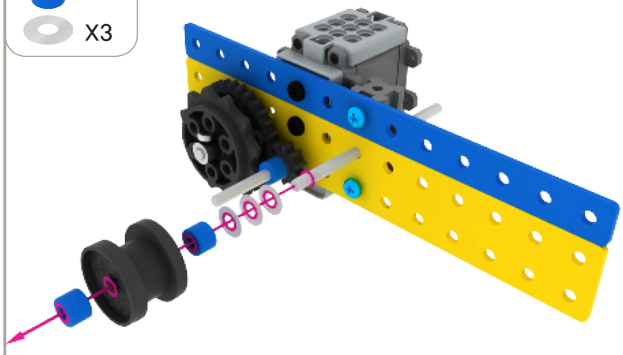
Connect DC motor line first

70mm

24

X2

X3



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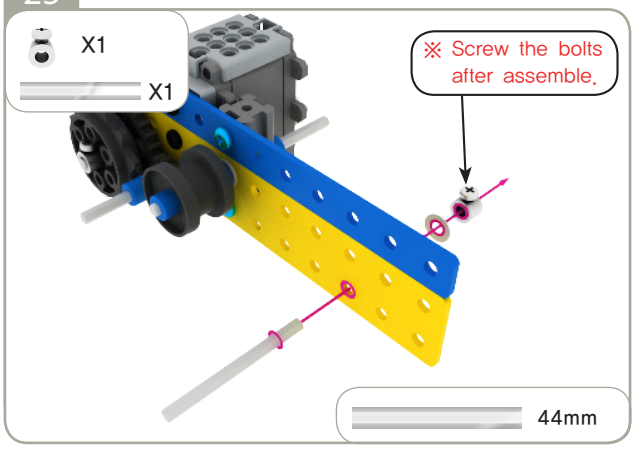

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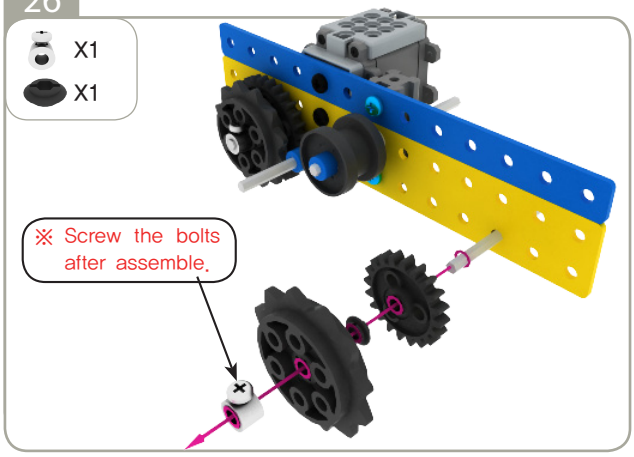

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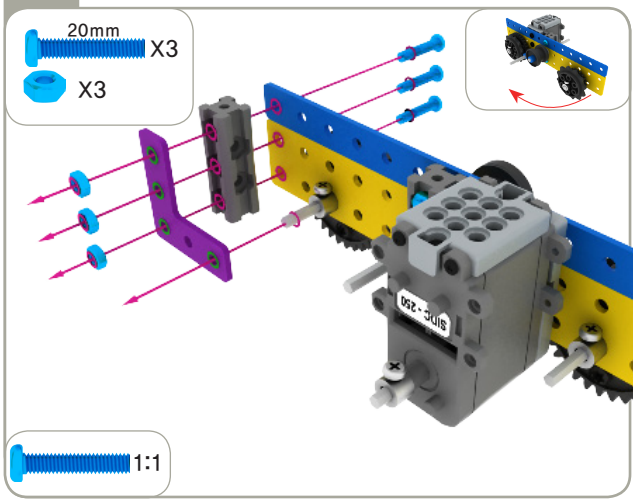

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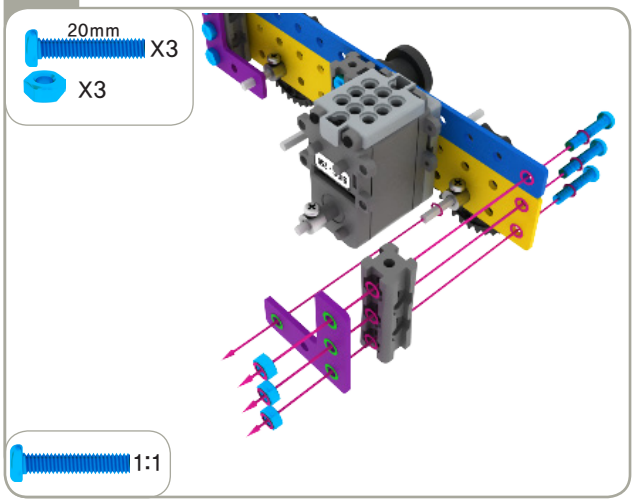

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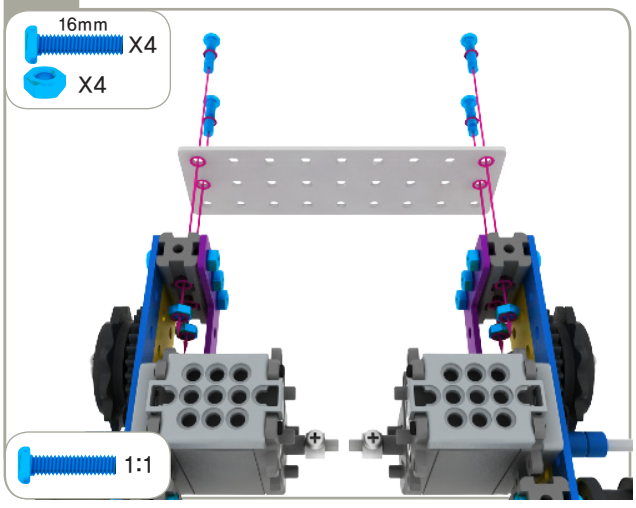

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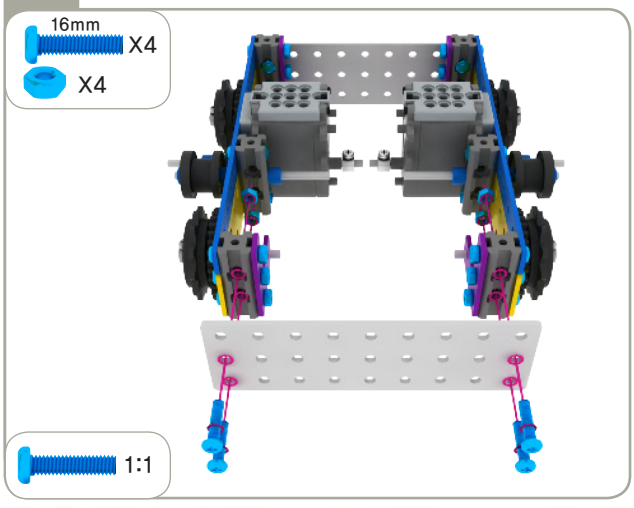

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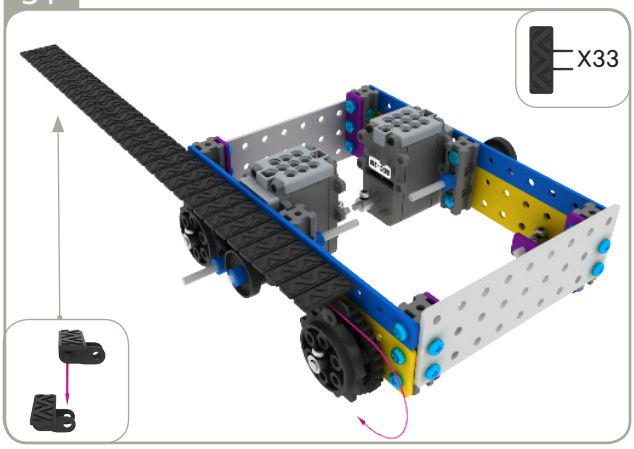

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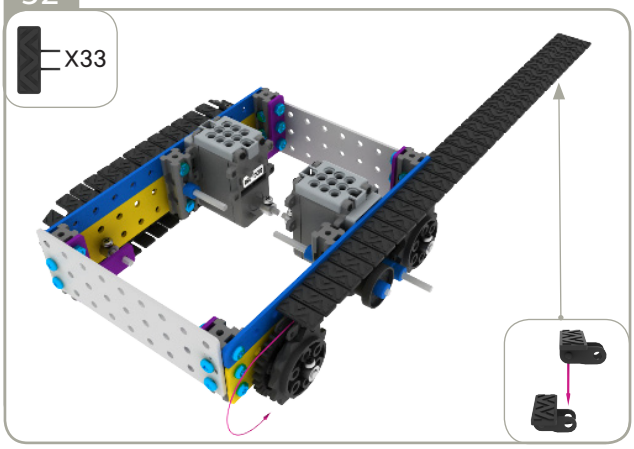

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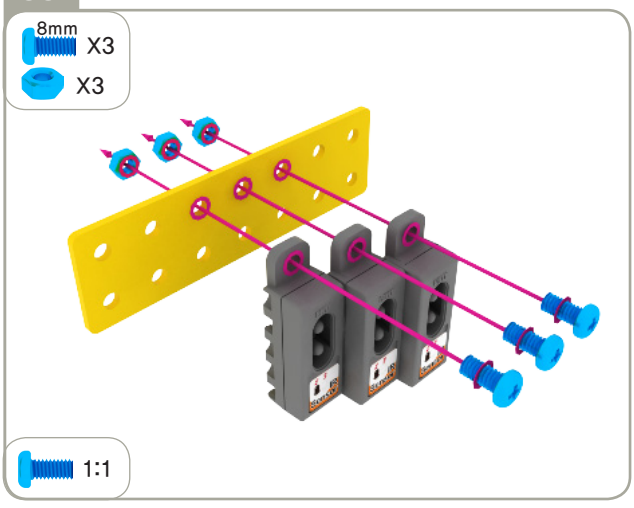

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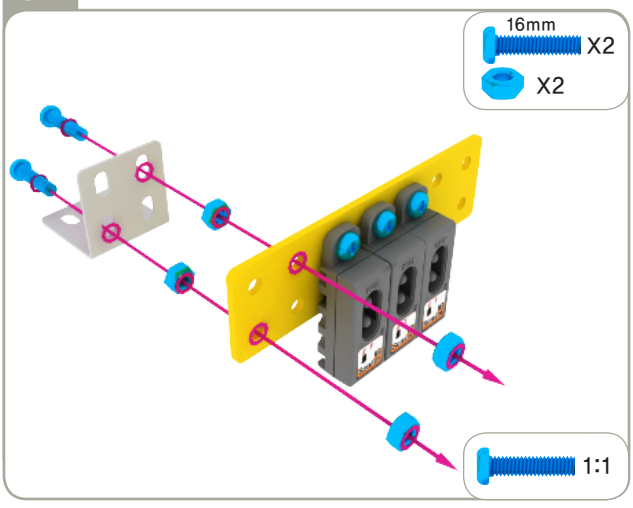

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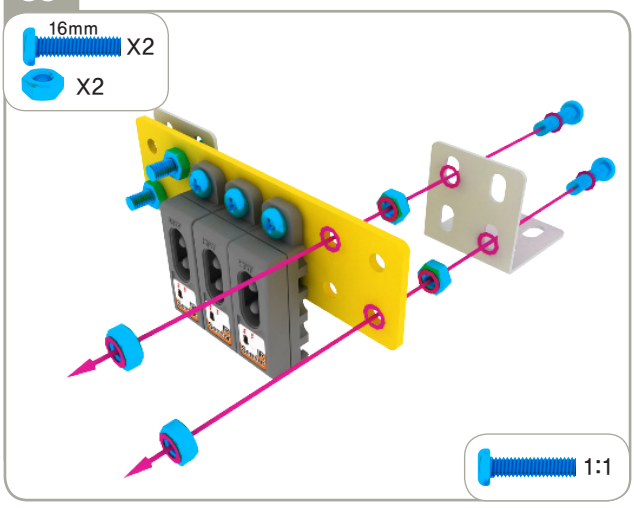

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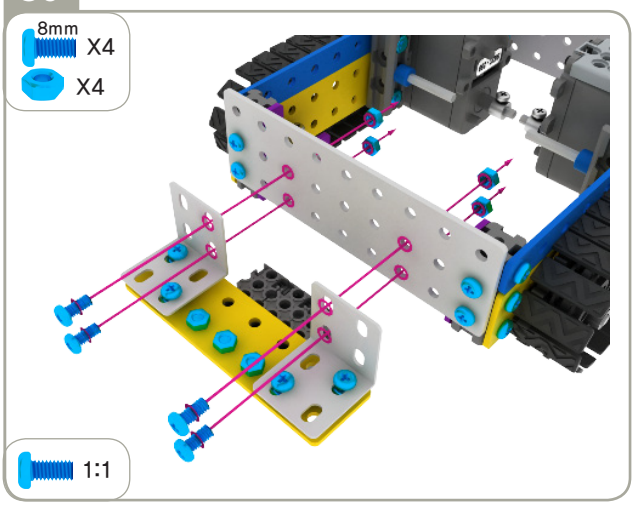
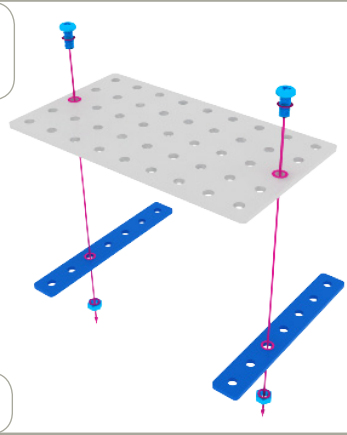


37

8mm X2

X2

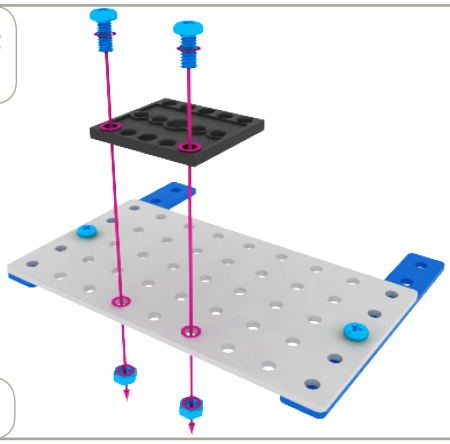


1:1

38

8mm X2

X2



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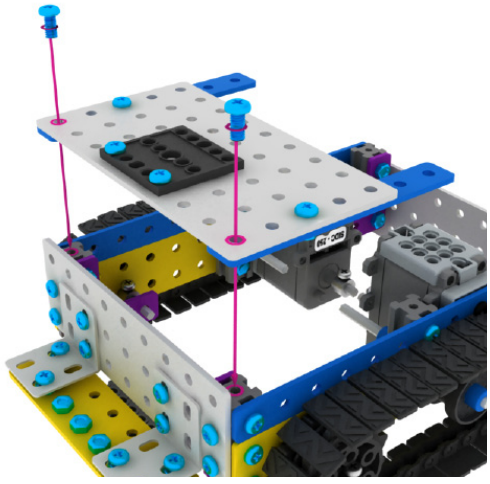
39

8mm X2



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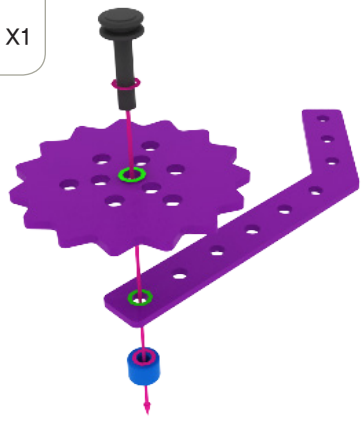
40

X1

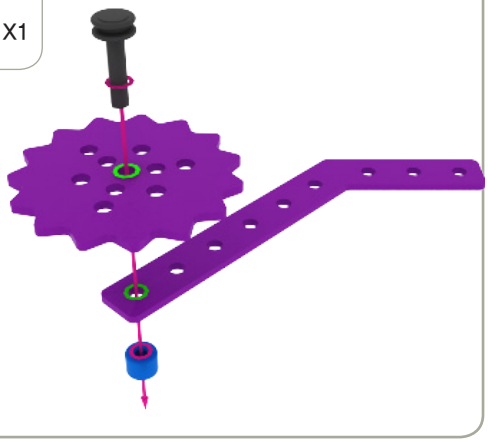
X1



41

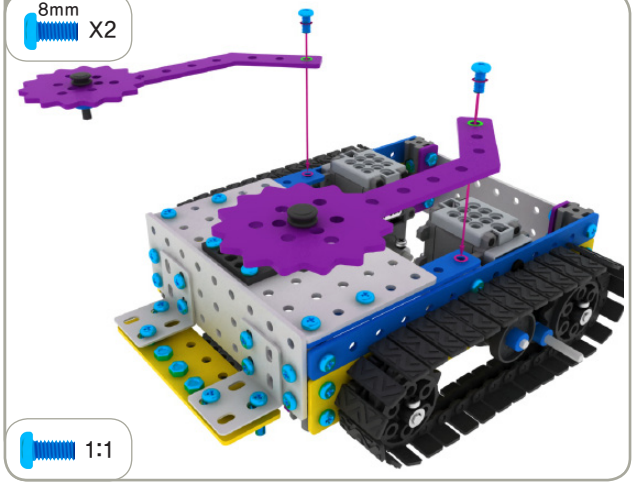
X1

X1



42

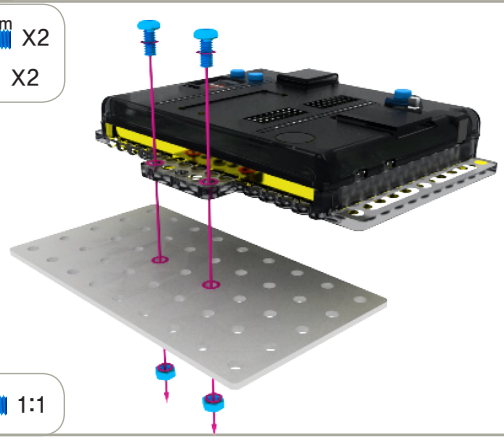
8mm X2



1:1

43

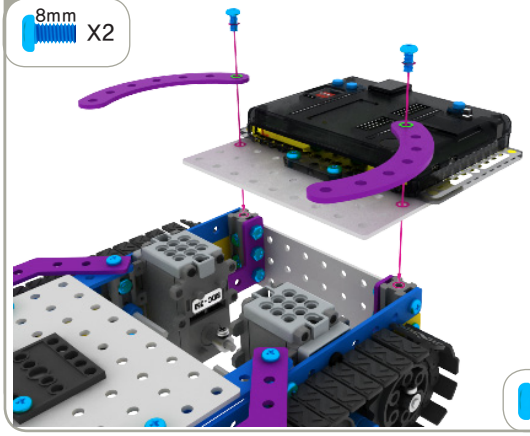
8mm X2
X2



1:1

44

8mm X2



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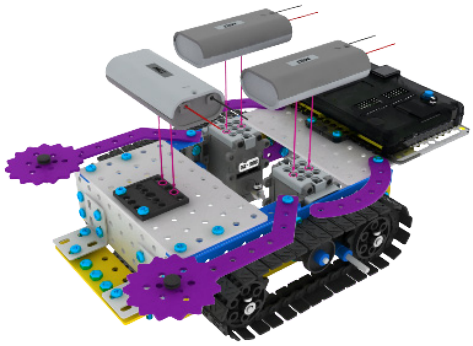
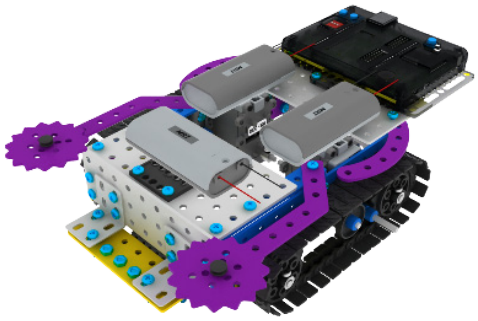
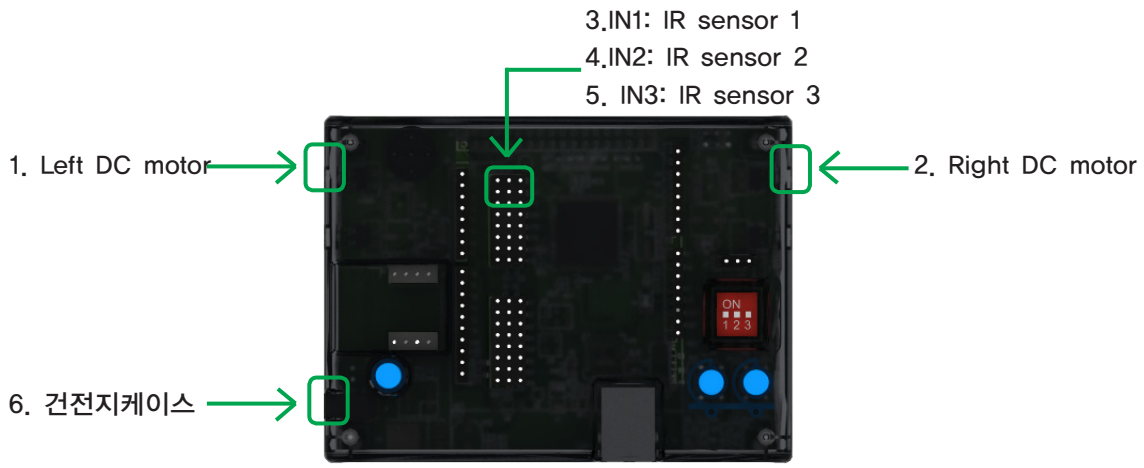
45



Complete

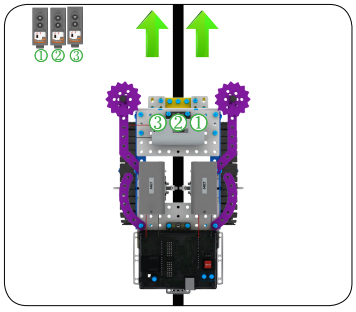


Connecting the mainboard

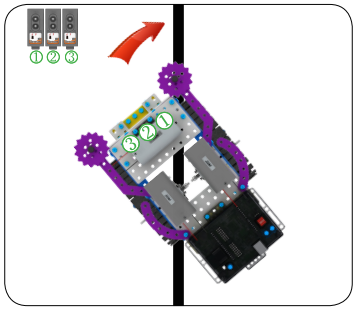


Please connect in this order:
1. Connect left DC motor to L–MOTOR connector.
2. Connect right DC motor to R–MOTOR connector.
3. Connect IR sensor1 to INPUT1 connector.
4. Connect IR sensor2 to INPUT2 connector.
5. Connect IR sensor3 to INPUT3 connector
6. Connect battery case to Power connector.

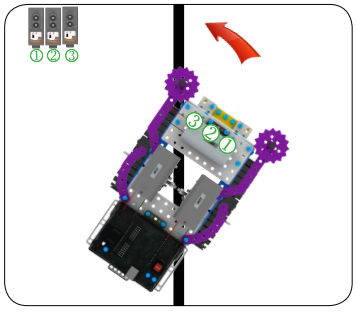
Motion Pattern



Recognize No.1 and 3 IR sensors, robot will go forward.



Recognize No.2 and 3 IR sensors, robot will turn right.



Recognize No.1 and 2 IR sensors, robot will turn left.

Learn to compile program in advance

※ Try to write down the program before we compile on software.

1. Recognize No.1 and 3 IR sensors, robot will go forward.
2. Recognize No.2 and 3 IR sensors, robot will turn left.
3. Recognize No.1 and 2 IR sensors, robot will turn right.

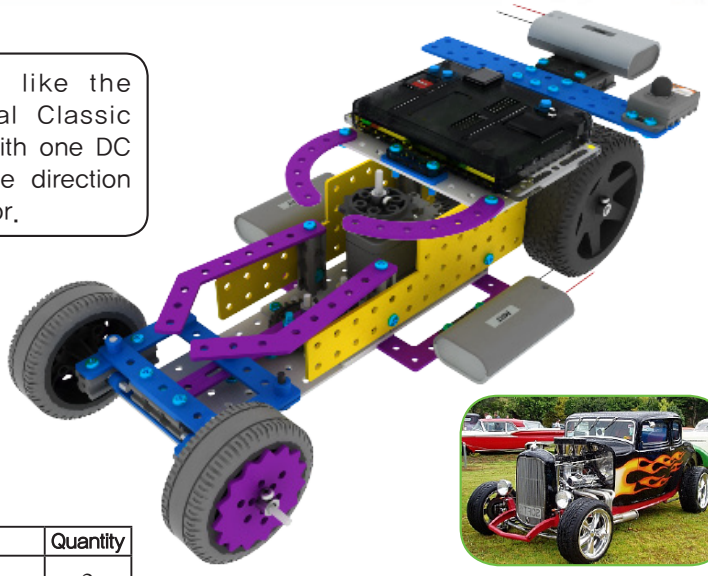
※ Program example : Refer to the back of book.

Program download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download to start".
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

Classic Car

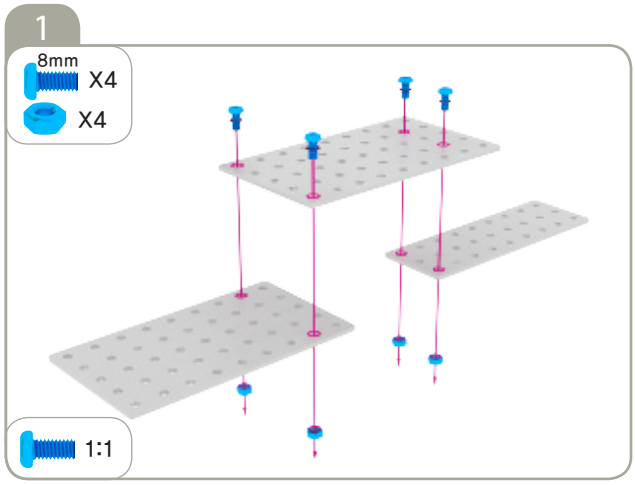
Classic Car looks like the Visualization of real Classic cars. Drive the car with one DC motor and control the direction with another DC motor.

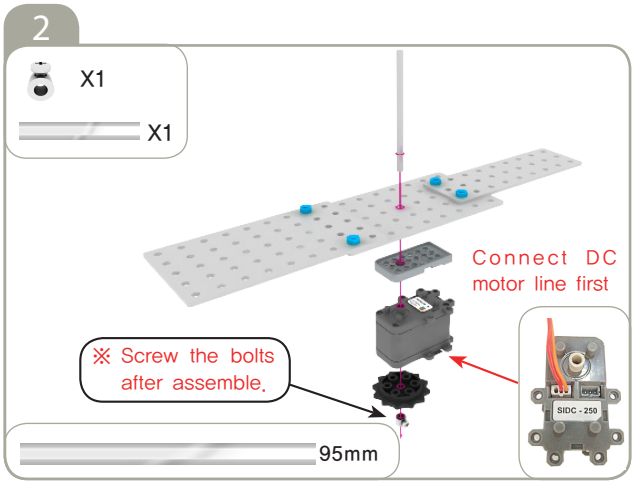


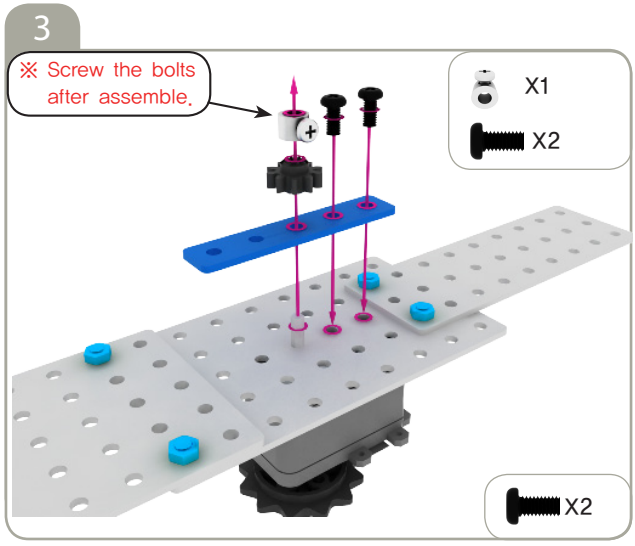
Name	Picture	Quantity
Steel shaft 31mm		2
Steel shaft 44mm		2
Steel shaft 70mm		2
Steel shaft 95mm		1
Steel shaft 120mm		1
13AL Frame		2
15AL Frame		4
17AL Frame		4
113AL Frame		2
27AL Frame		2
213AL Frame		2
39AL Frame		2
59AL Frame		2
4–5 Pillar block		4
2–3 Pillar Block		8
Motor Mount		3

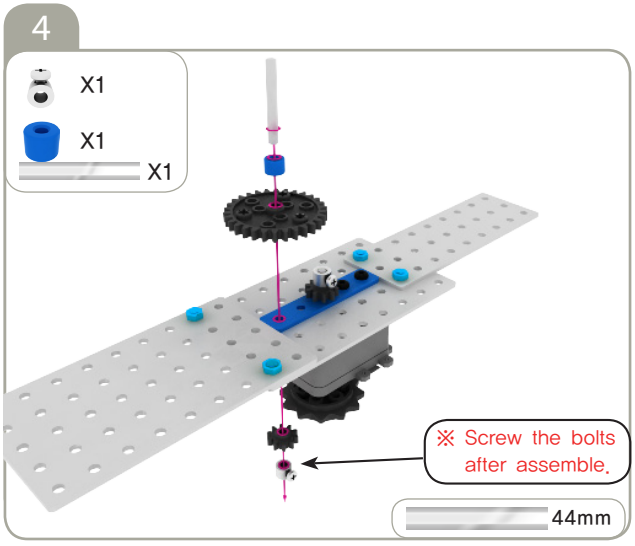
Name	Picture	Quantity
9V Battery Case		1
MRT5–1 Main board		1
DC MOTOR		2
Remote Controller		1
AL Frame90		4
AL Sprocket		2
L17AL Frame		1
AL Round Block		2
AL Frame135		2

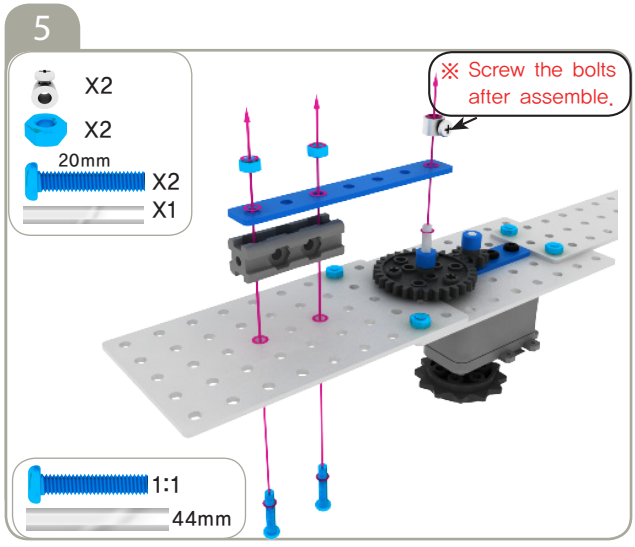
Name	Picture	Quantity
Bolt		2
Bolt 8mm		26
Bolt 16mm		21
Bolt 20mm		5
Nut		40
ABS Connecting shaft		3
B–Bush		9
Washer		2
S–Gear		2
Guide Wheel		2
M–Gear		2
L–Gear		2
Sprocket		1
Sleeve pipe		10
Big Wheel1		2
Big Wheel2		2
RC Receiver		1

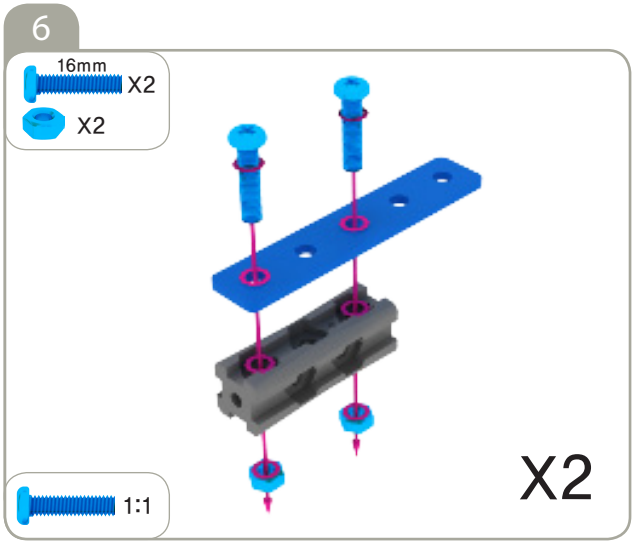

1
8mm
X4
X4
1:1


2
X1
X1
Connect DC motor line first
※ Screw the bolts after assemble.
SIDC - 250
95mm

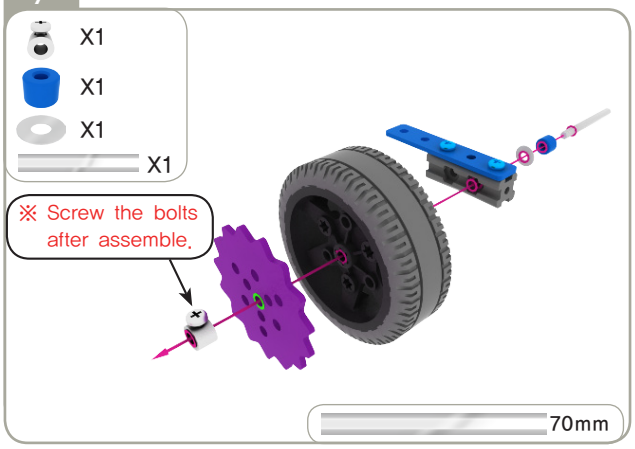

3
※ Screw the bolts after assemble.
X1
X2
X2


4
X1
X1
X1
※ Screw the bolts after assemble.
44mm

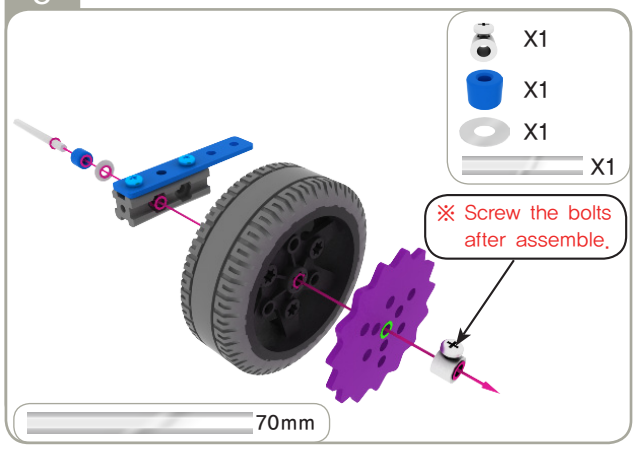

5
X2
X2
20mm
X2
X1
※ Screw the bolts after assemble.
1:1
44mm


6
16mm
X2
X2
1:1
X2

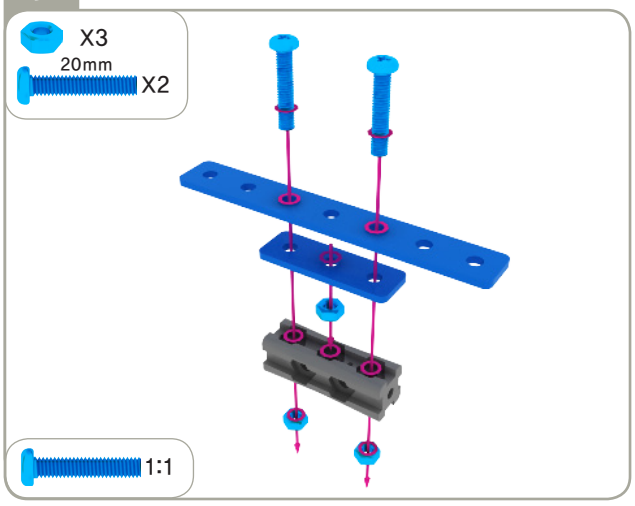
7


X1
X1
X1
X1
※ Screw the bolts after assemble.
70mm

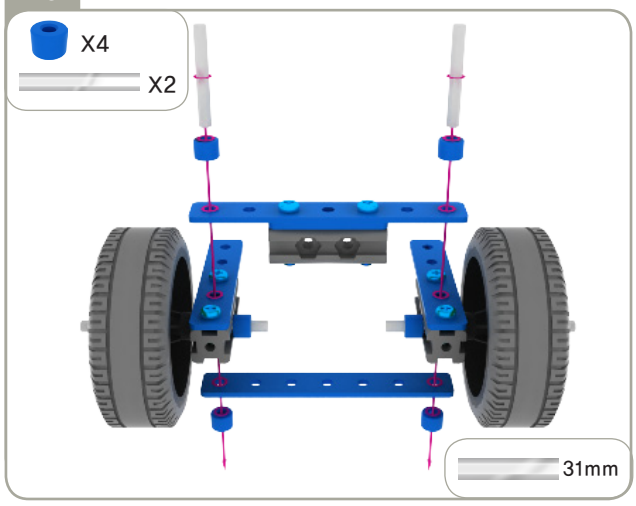
8


X1
X1
X1
X1
※ Screw the bolts after assemble.
70mm

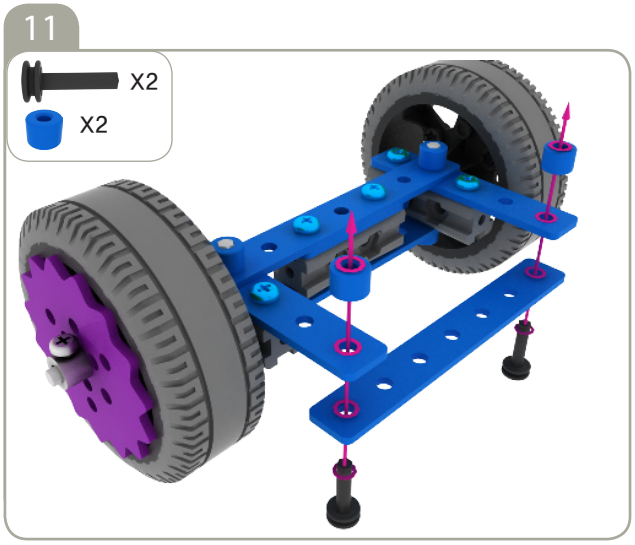
9


X3
20mm
X2
1:1

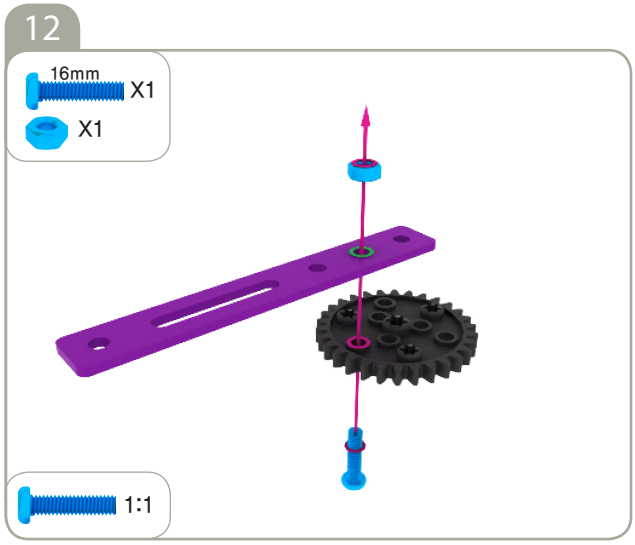
10


X4
X2
31mm

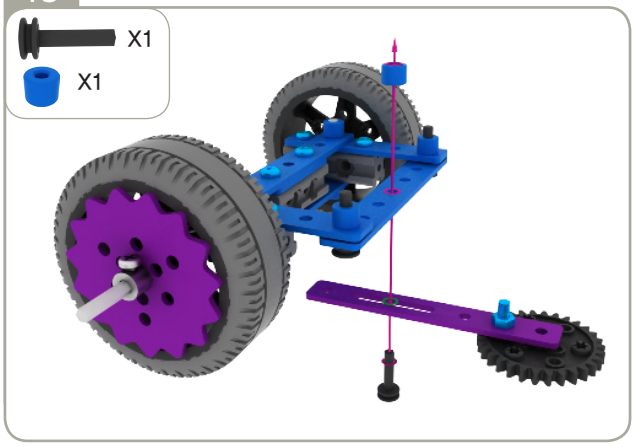
11


X2
X2

12


16mm
X1
X1
1:1

13



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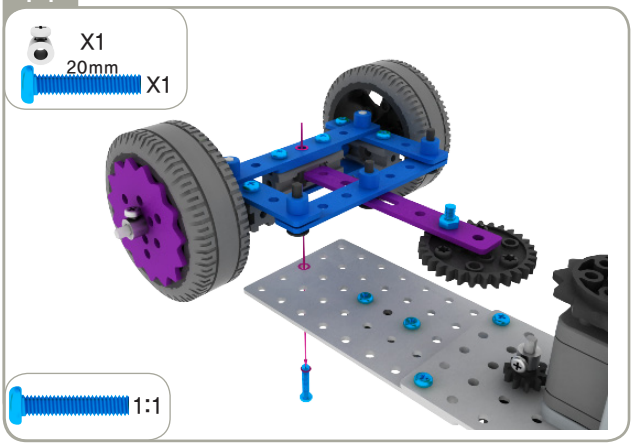

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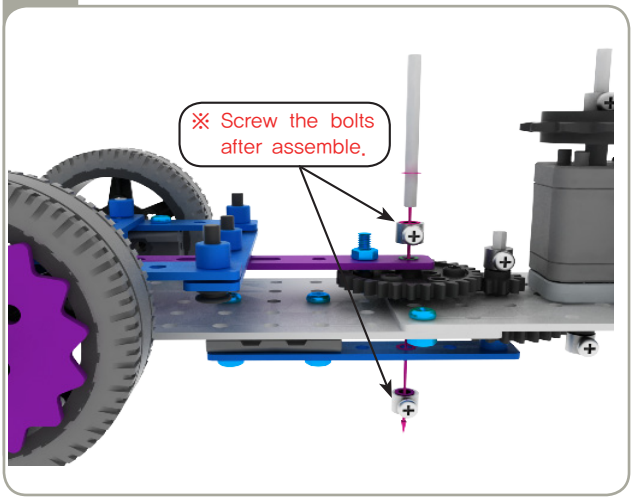

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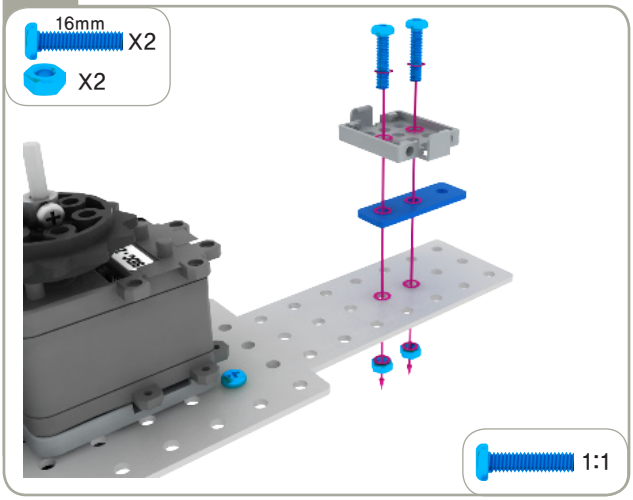

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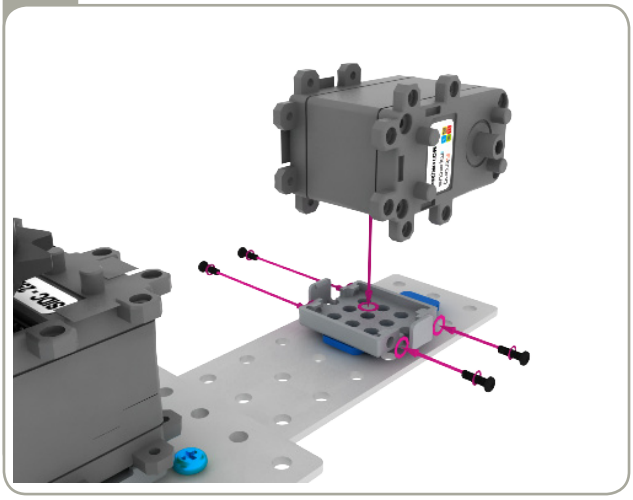

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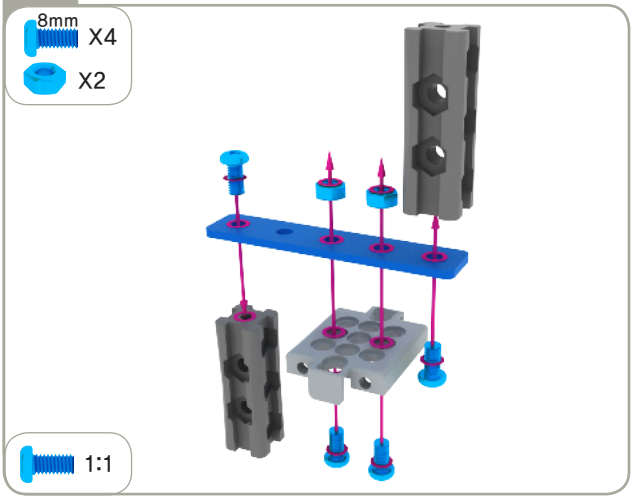

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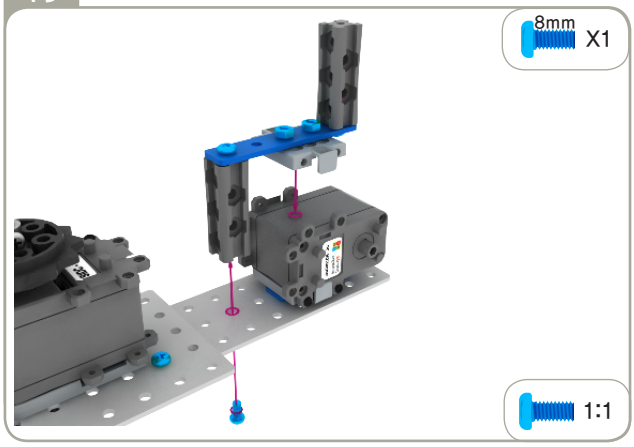

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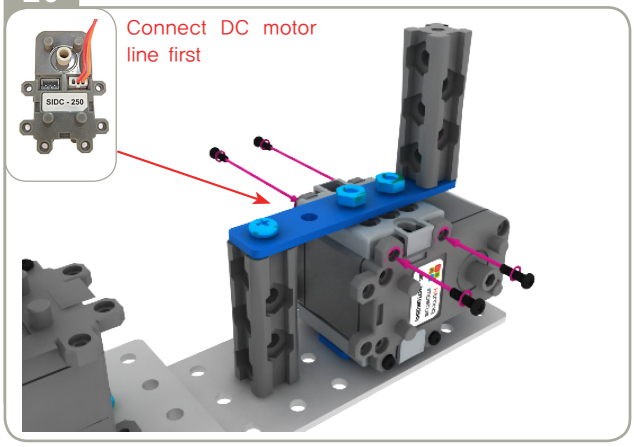

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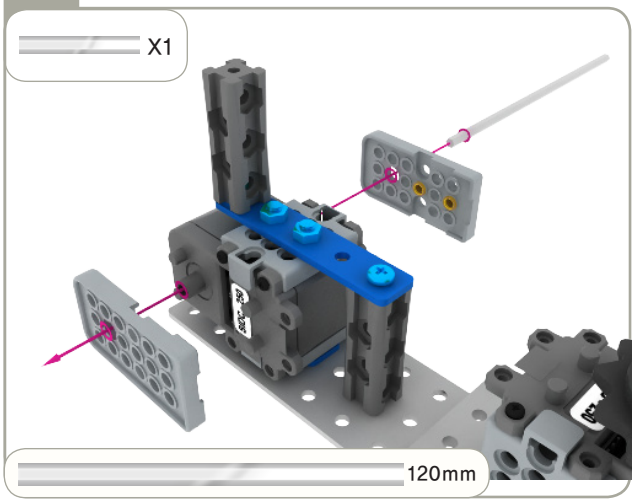

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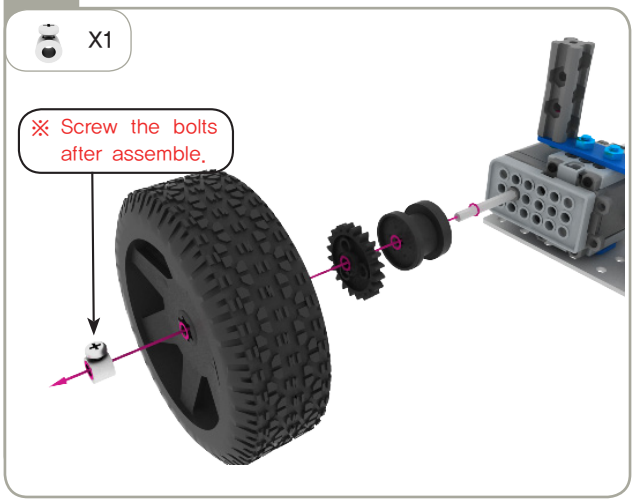

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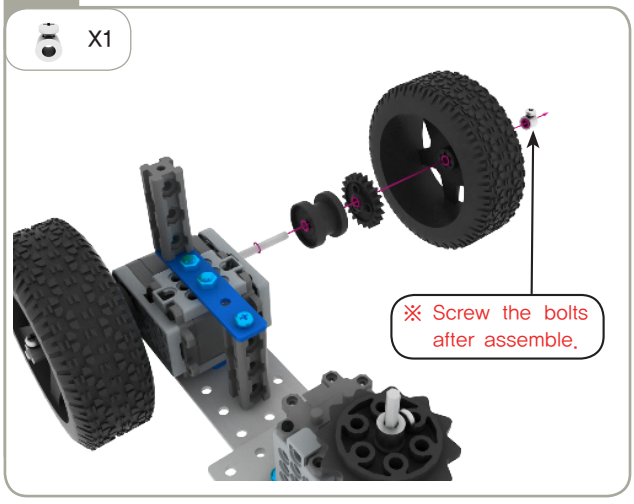

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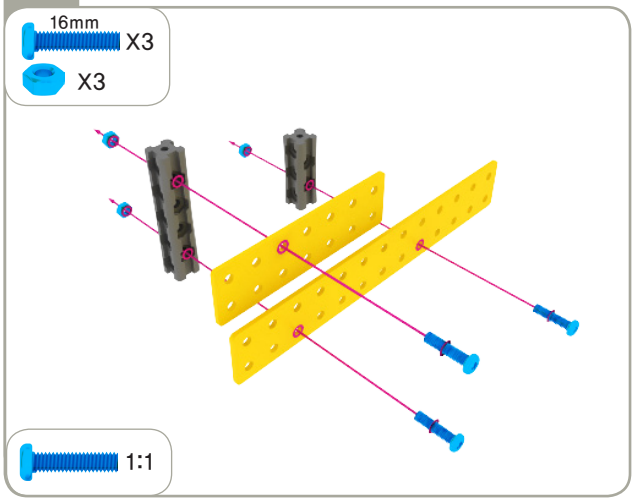
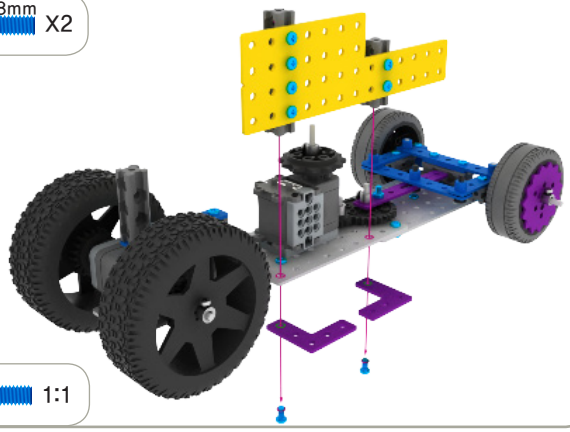


25

8mm X2

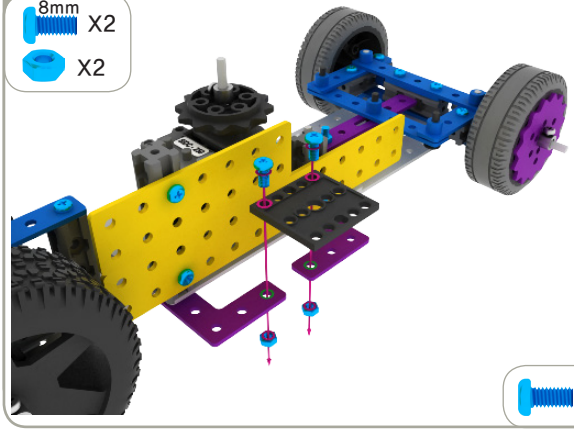


1:1

26

8mm X2

X2

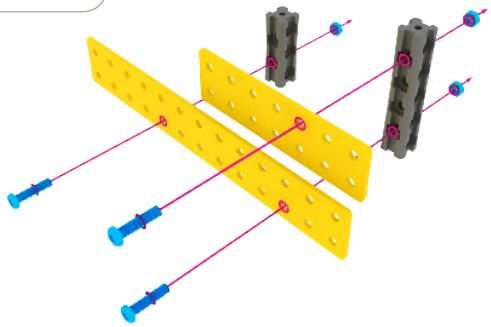


1:1

27

16mm X3

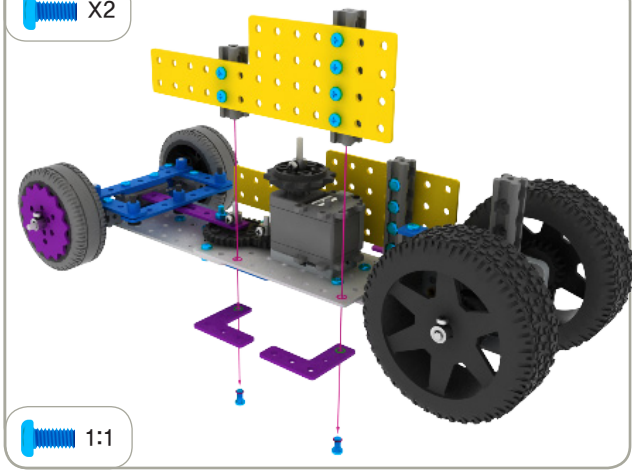
X3



1:1

28

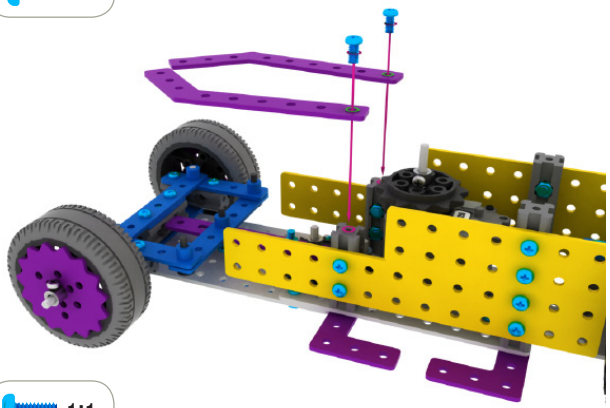
8mm X2



1:1

29

8mm X2

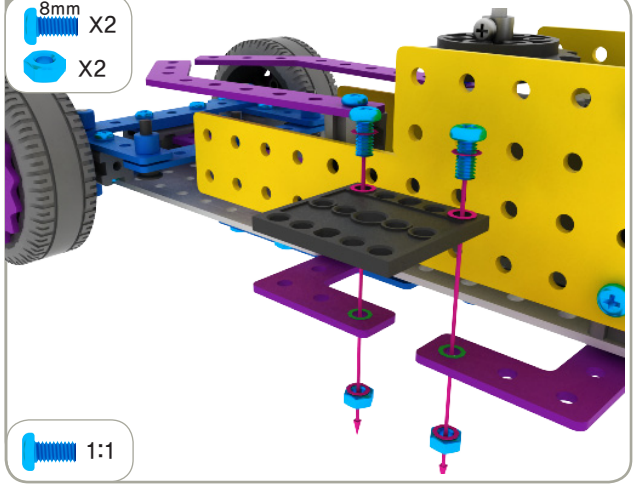


1:1

30

8mm X2

X2

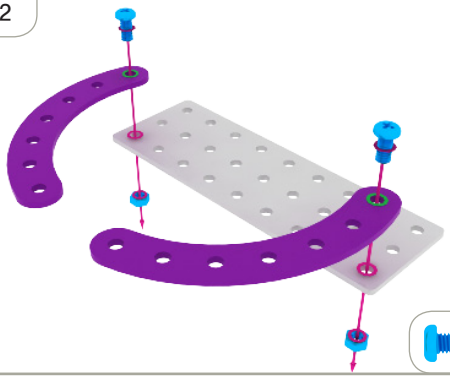


1:1

31

8mm X2

X2



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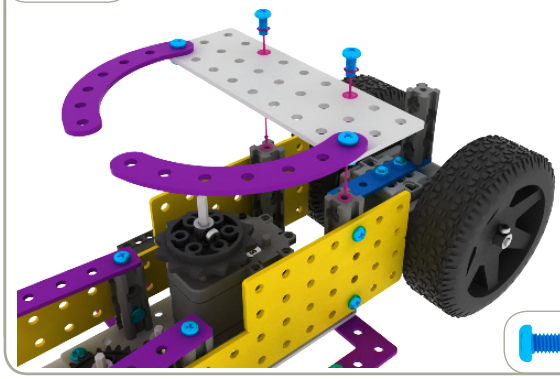
32

8mm X2



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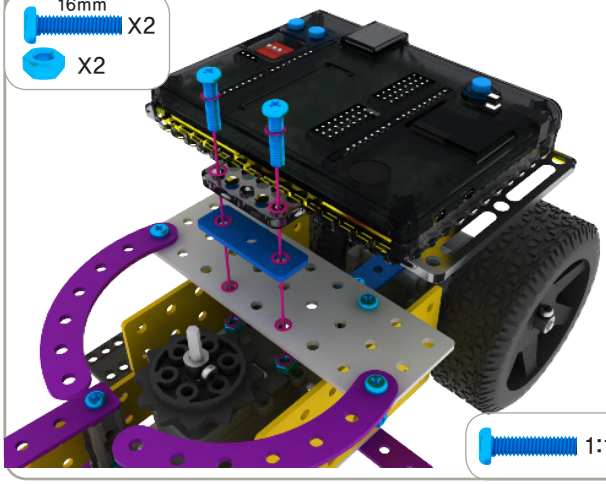
33

16mm X2

X2

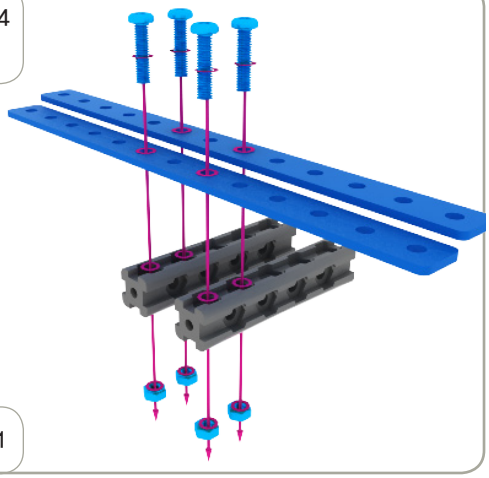


1:1

34

16mm X4

X4

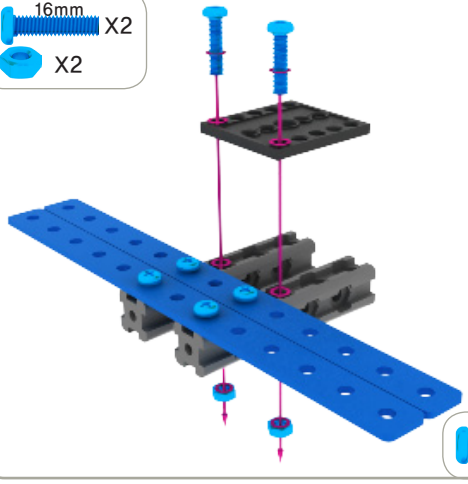


1:1

35

16mm X2

X2

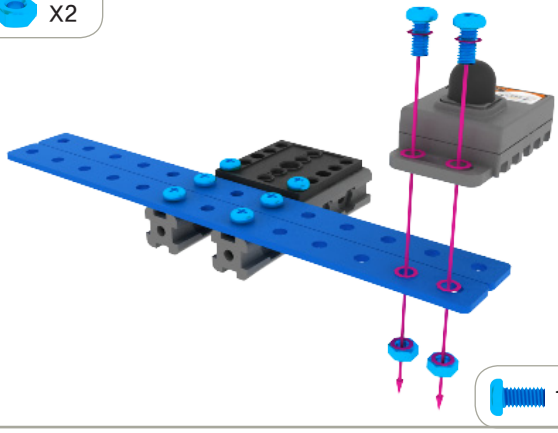


1:1

36

8mm X2

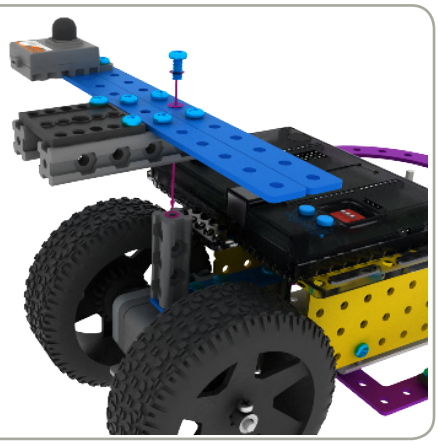
X2



1:1

37

8mm X1



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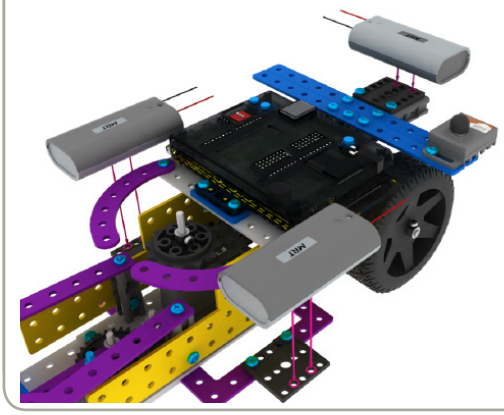
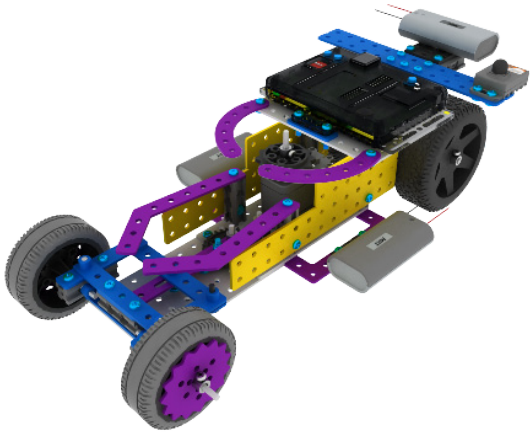
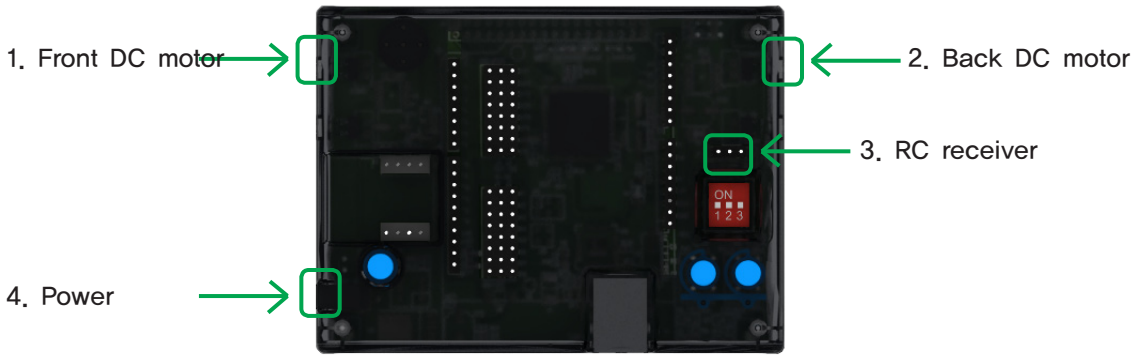
38



Complete



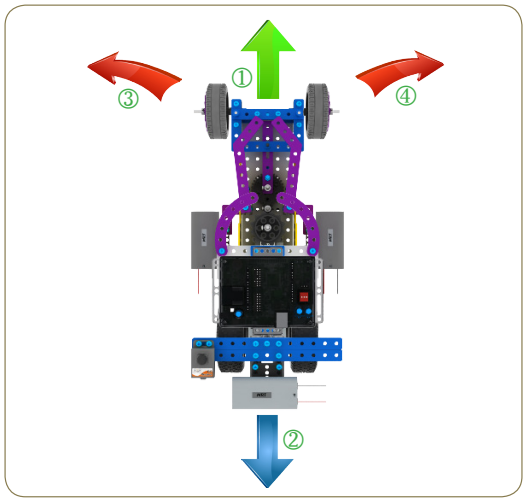
Connecting the mainboard



Connect in this order :

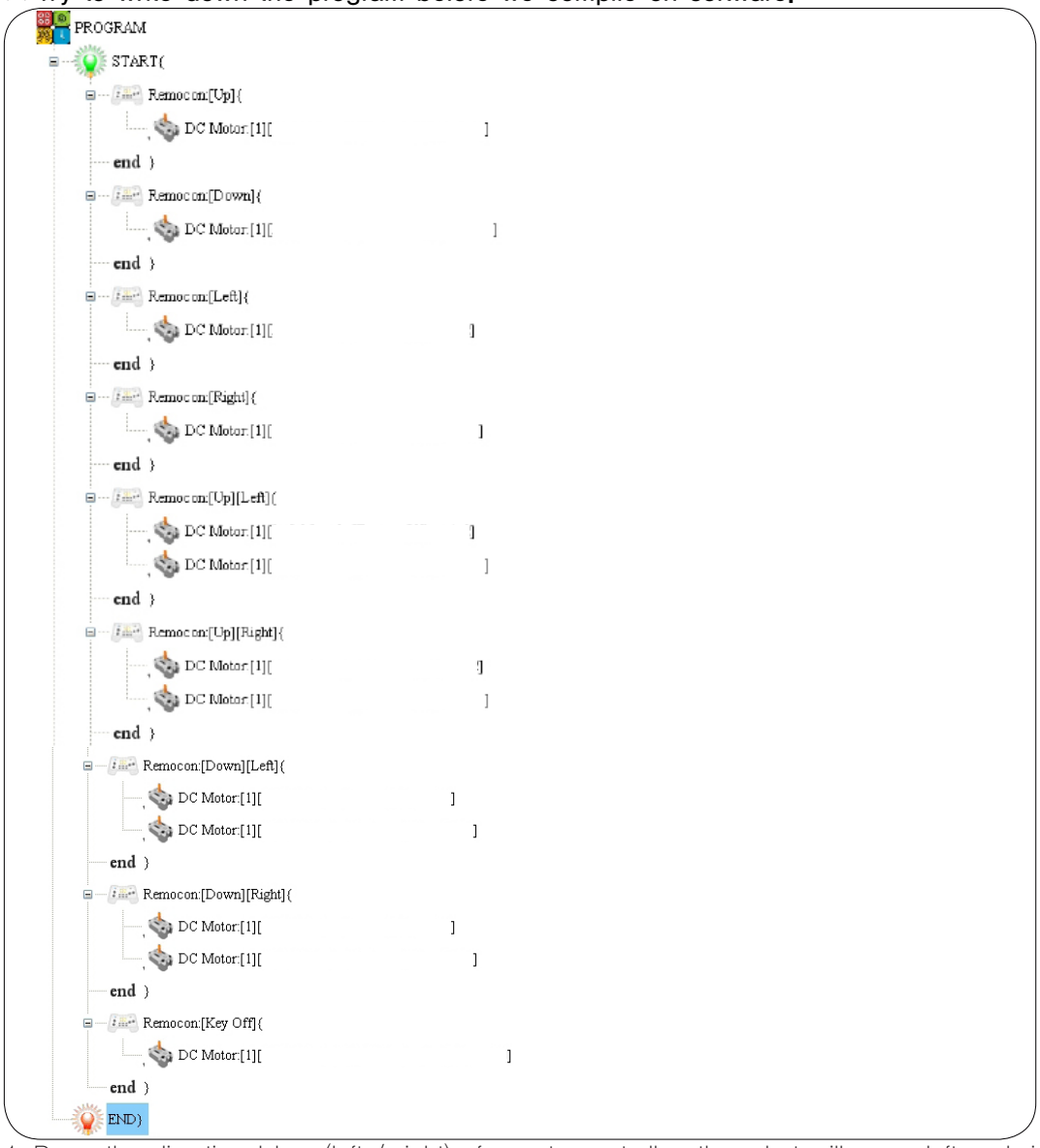
1. Connect left DC motor to L–MOTOR connector1.
2. Connect right DC motor to R–MOTOR connector 2.
3. Connect RC receiver to R/C connector.
4. Connect battery case to POWER connector.

Motion Pattern



Learn to compile program in advance

※ Try to write down the program before we compile on software.



1. Press the directional key (left / right) of remote controller, the robot will move left and right .
2. Press the directional key (left / right) of remote controller, the robot will move left and right .

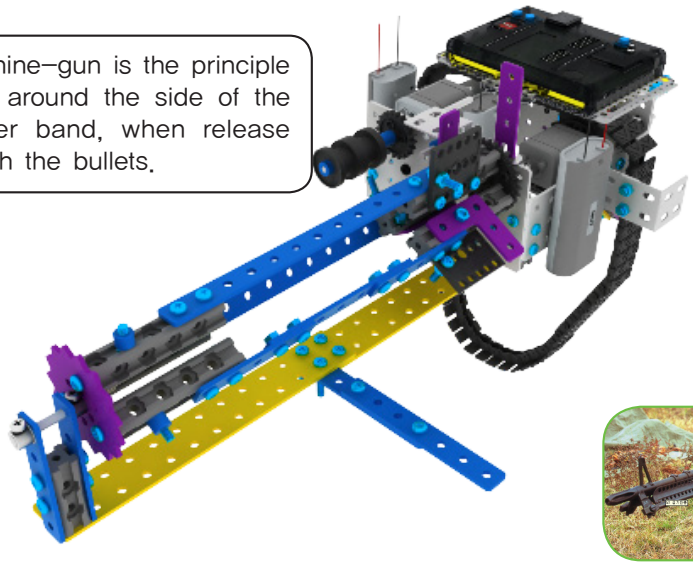
※ Program example : Refer to the back of book.

Program download

1. Compile program
2. Confirm the Battery case, DC motor and other sensors are all connected to the right connectors.
3. Connect the download cable.
4. Press"SAVE" on the compile window and then press "Download to start".
5. Turn on the power or press "Restart" button when the "download" window opens.
6. Once the download is completed, remove the download cable and turn the power off and then on.

MACHINE GUN

30 bursts of machine–gun is the principle of wrapping wire around the side of the barrel with rubber band, when release the line will launch the bullets.

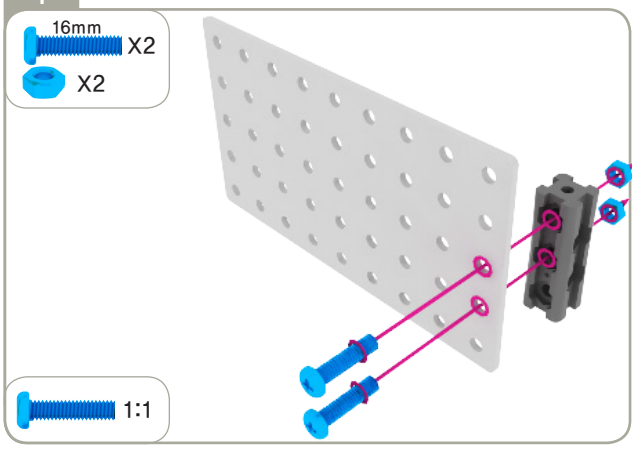


Name	Picture	Quantity
Steel shaft 31mm		2
Steel shaft 44mm		2
Steel shaft 70mm		1
Steel shaft 120mm		1
15AL Frame		4
17AL Frame		3
113AL Frame		2
27AL Frame		2
213AL Frame		2
39AL Frame		2
59AL Frame		2
Motor Mount		3
Caterpillar		80

Name	Picture	Quantity
9V Battery Case		1
MRT5–1 Main board		1
DC MOTOR		2
AL Frame90		3
AL Sprocket		1
17AL Frame		1
AL Frame135		2
4–5 Pillar block		6
2–3 Pillar Block		8

Name	Picture	Quantity
Bolt		2
Bolt 8mm		38
Bolt 16mm		36
Bolt 20mm		13
Nut		64
B–Bush		9
Washer		4
Guide Wheel		2
M–Gear		1
L–Gear		1
Sprocket		1
Sleeve pipe		10
Touch Sensor		1
D90 S–Bracket		4
D135 S–Bracket		1

1



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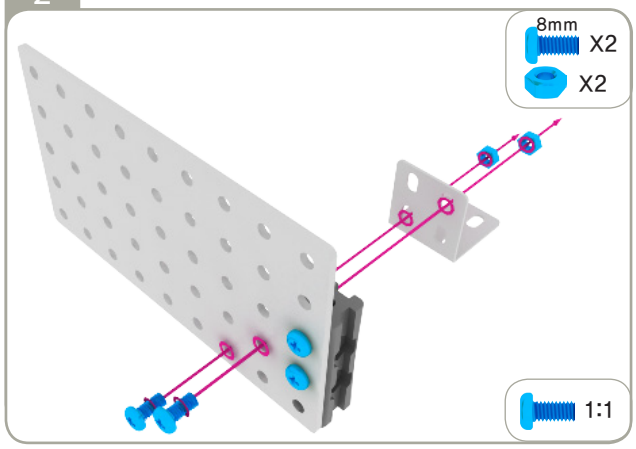

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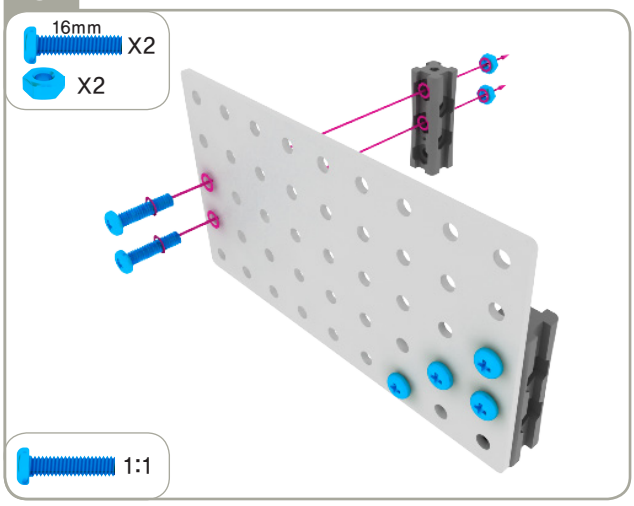
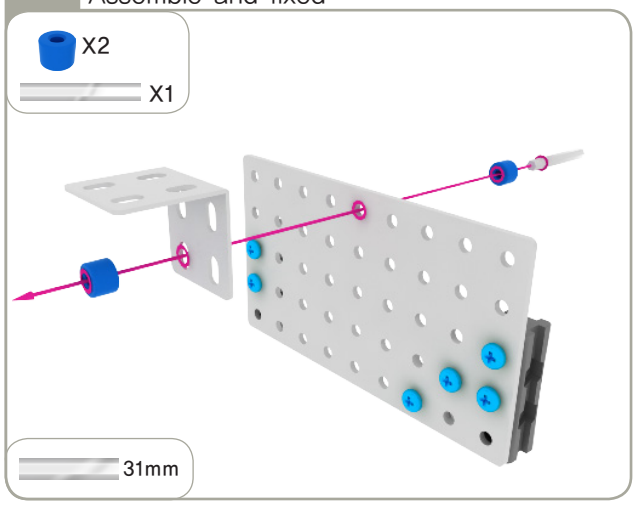


4 Assemble and fixed



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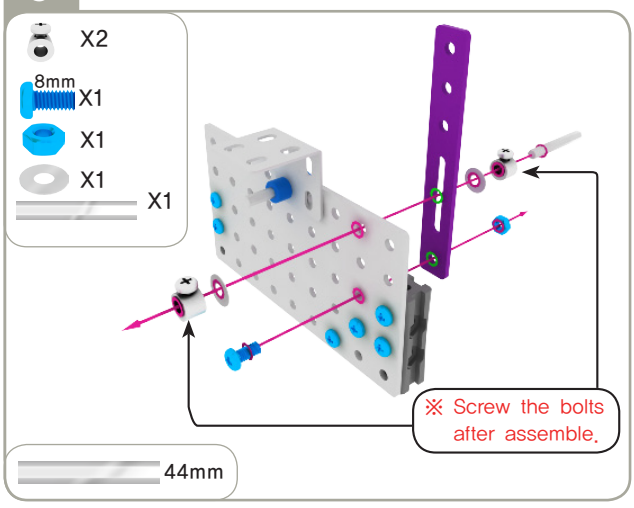

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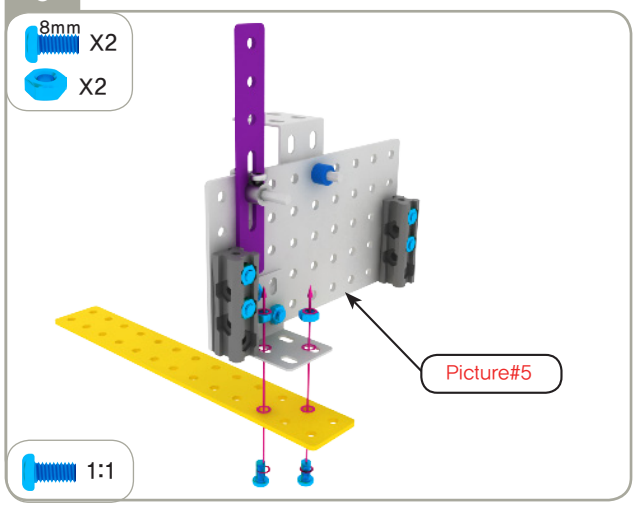
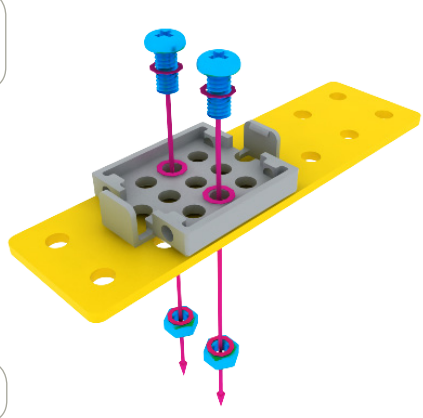


7

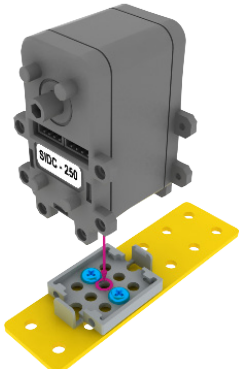
8mm X2

X2



1:1

8



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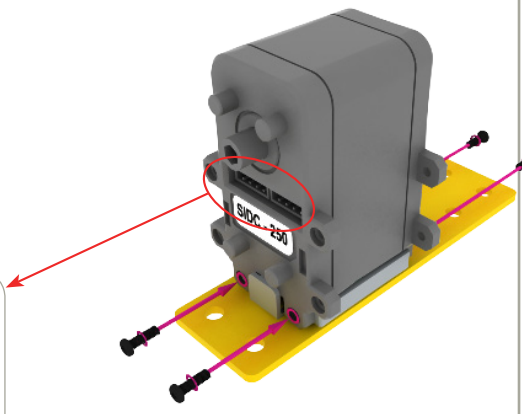
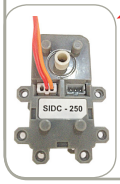


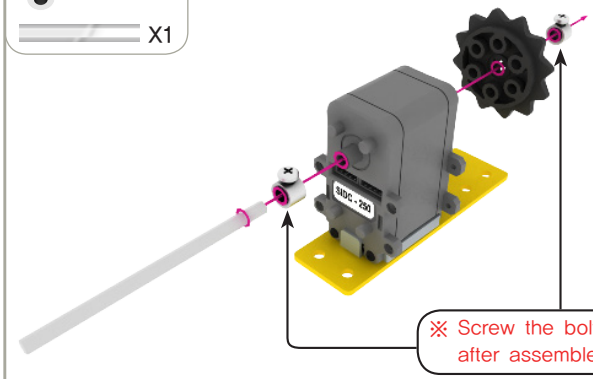


Connect DC motor line first

10

X2

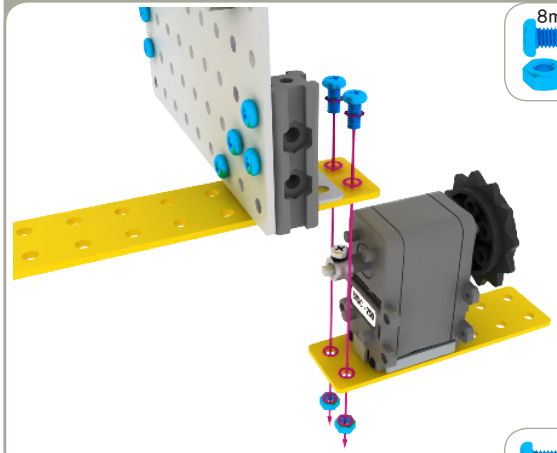
X1



※ Screw the bolts after assemble.

70mm

11

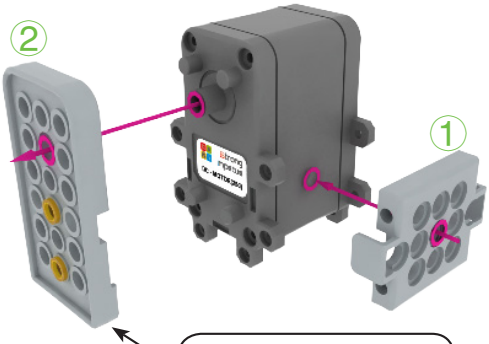


8mm X2

X2

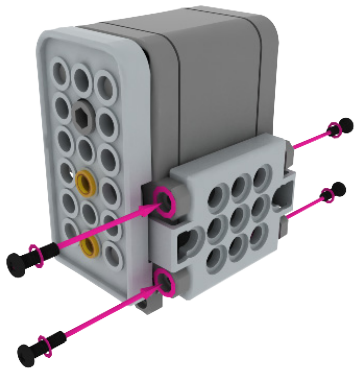
1:1

12



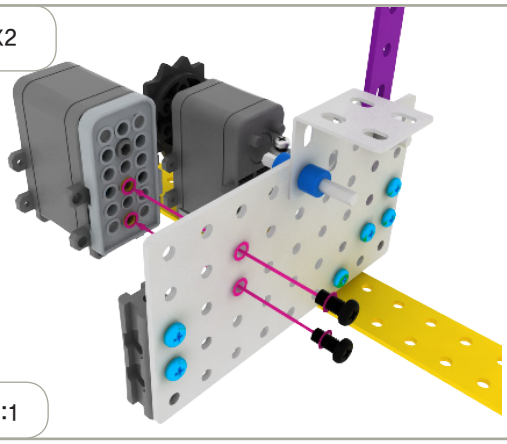
Use the insert module to fix frame.

13



14

X2



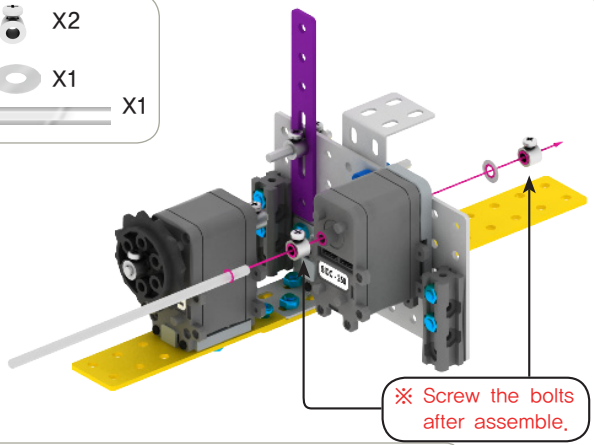
1:1

15

X2

X1

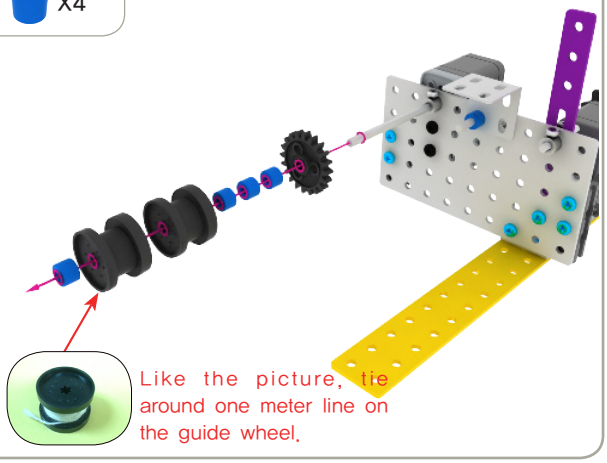
X1



120mm

15

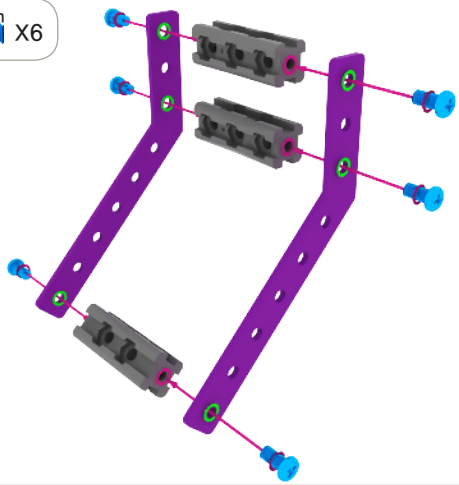
X4



Like the picture, tie around one meter line on the guide wheel.

17

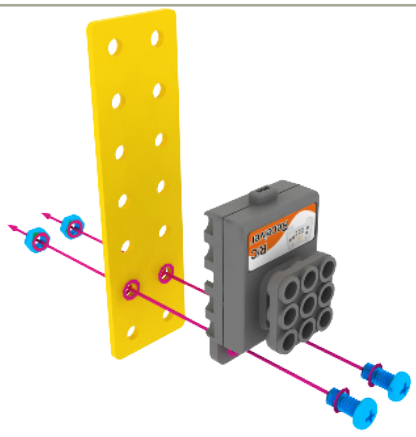
8mm X6



18

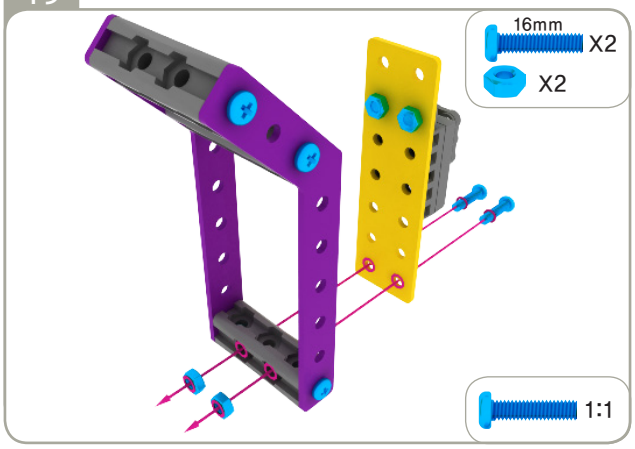
8mm X2

X2



1:1

19



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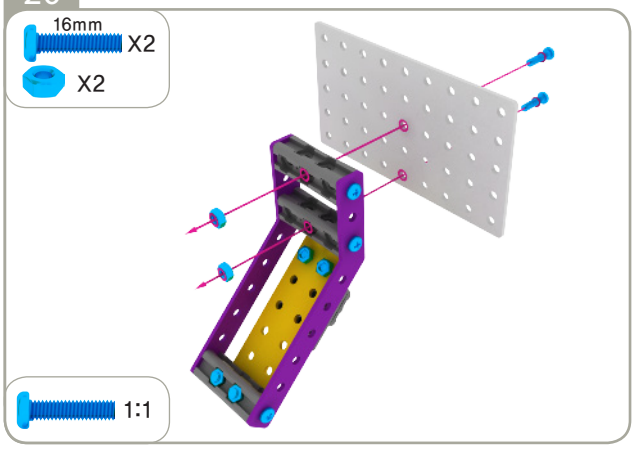

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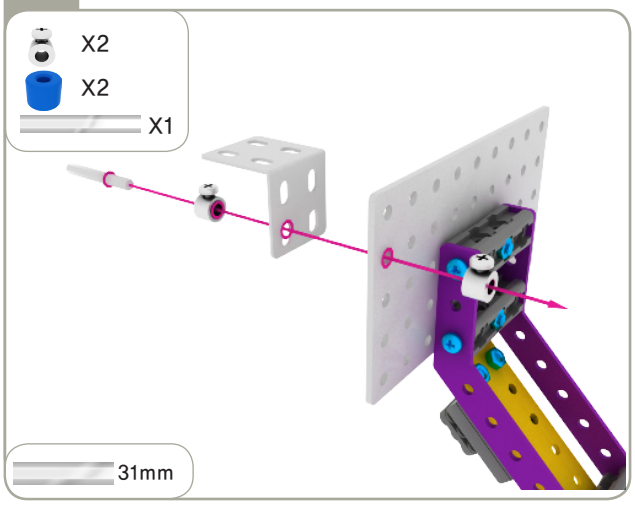

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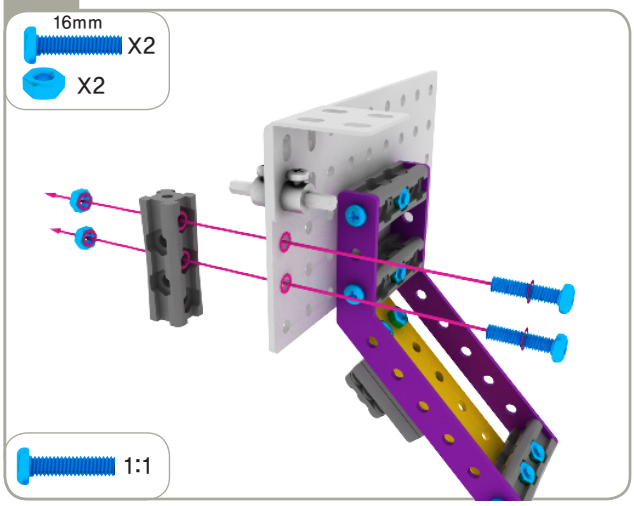

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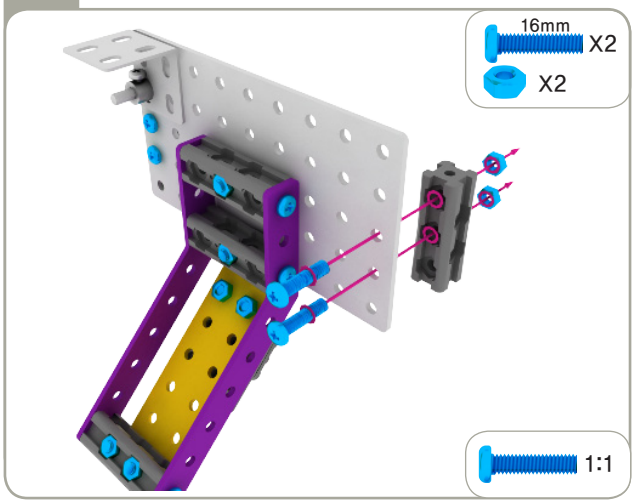

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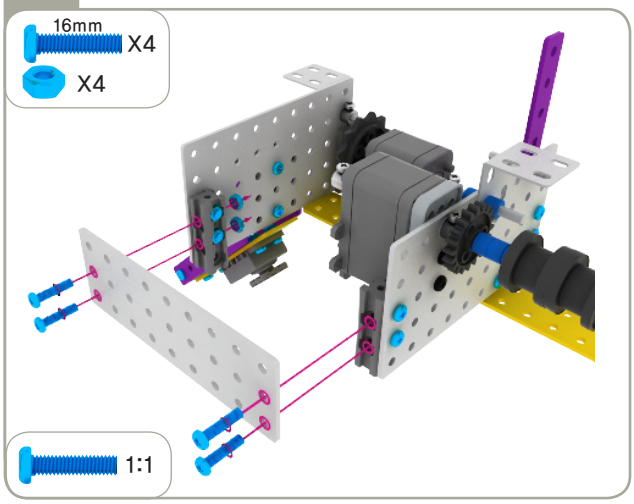

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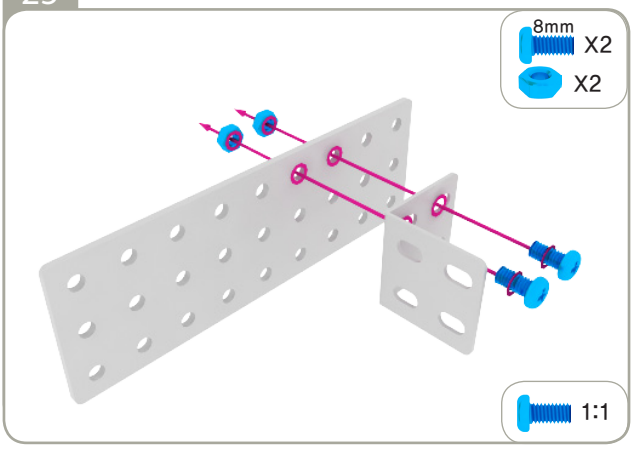

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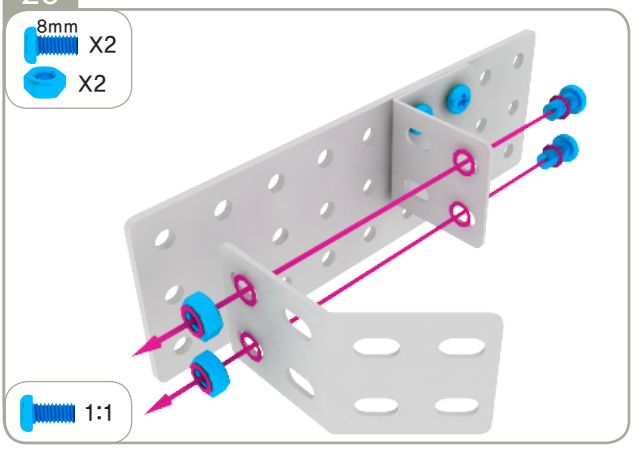

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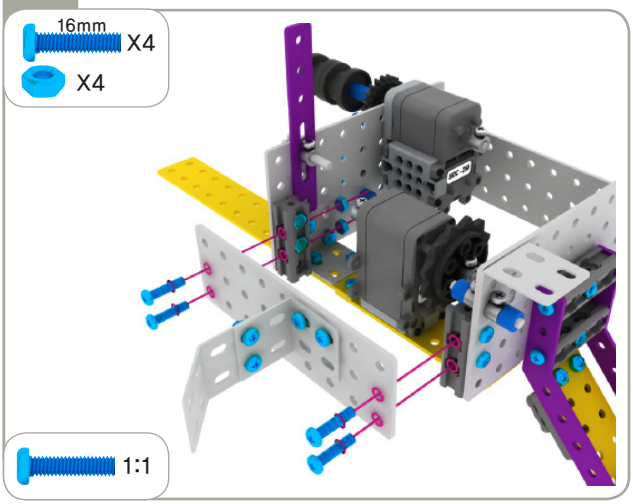

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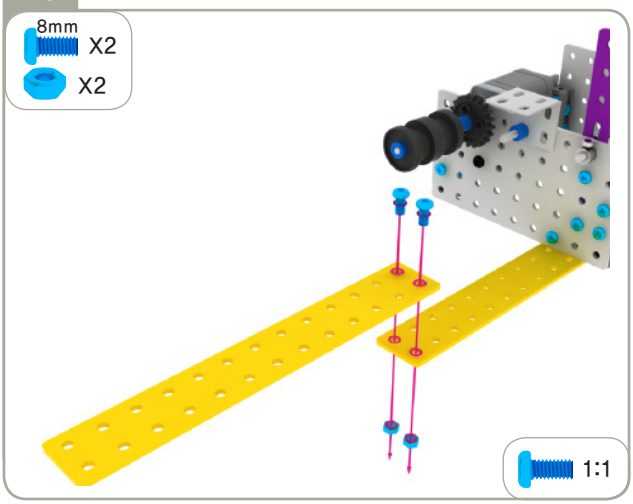

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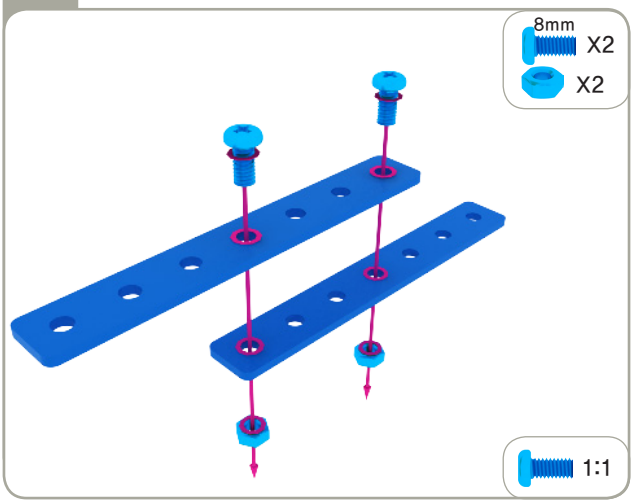

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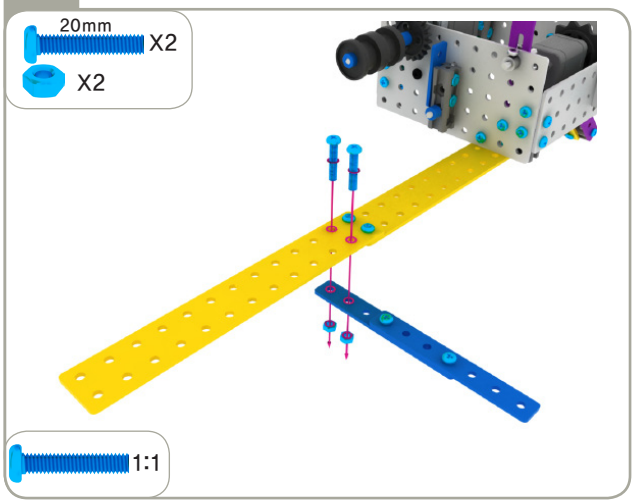

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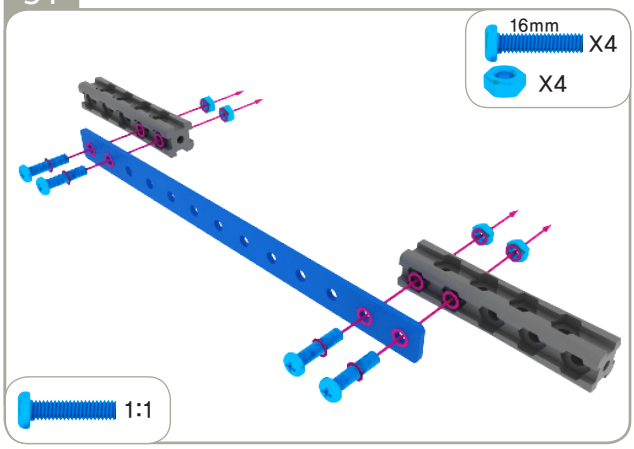

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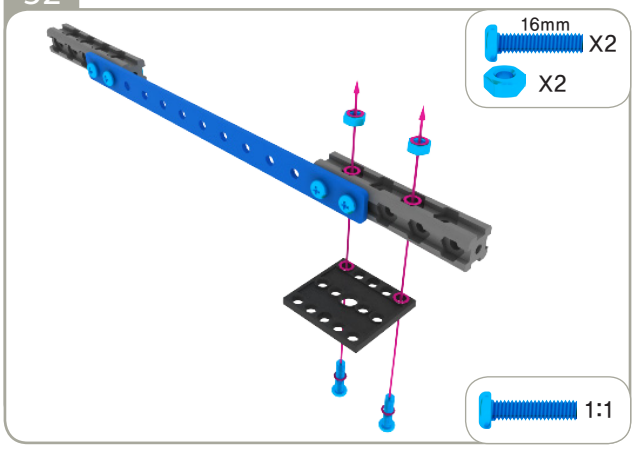

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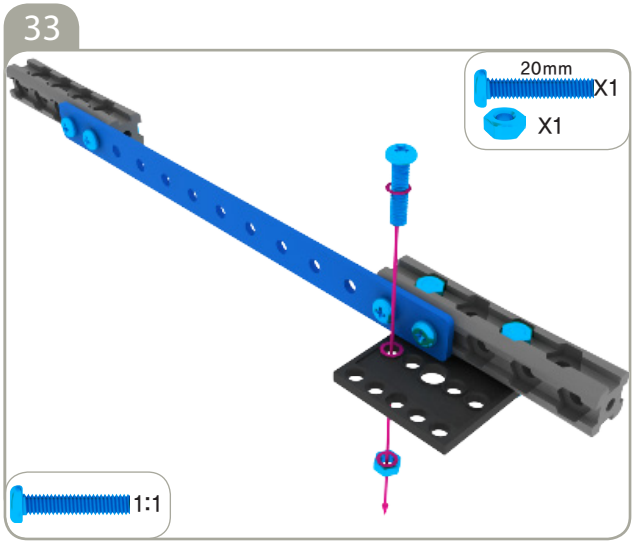

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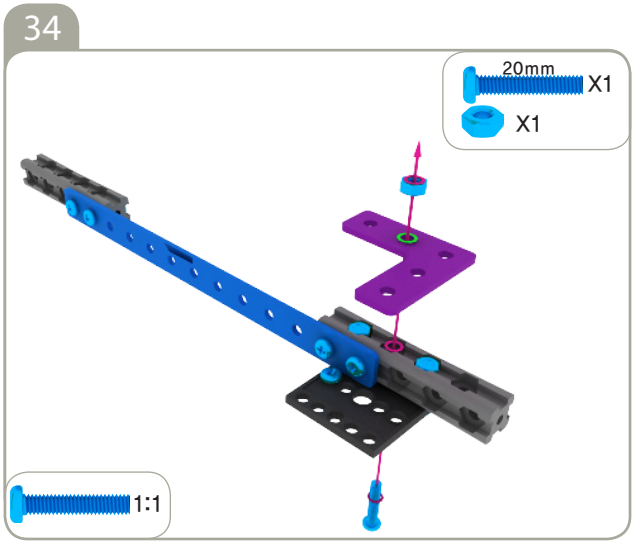

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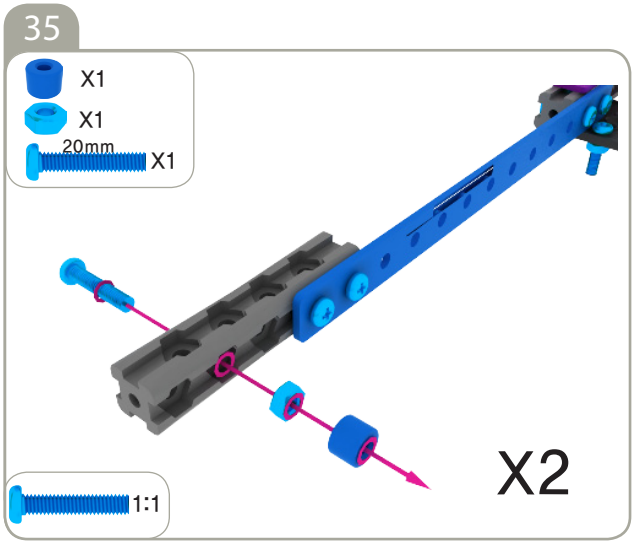

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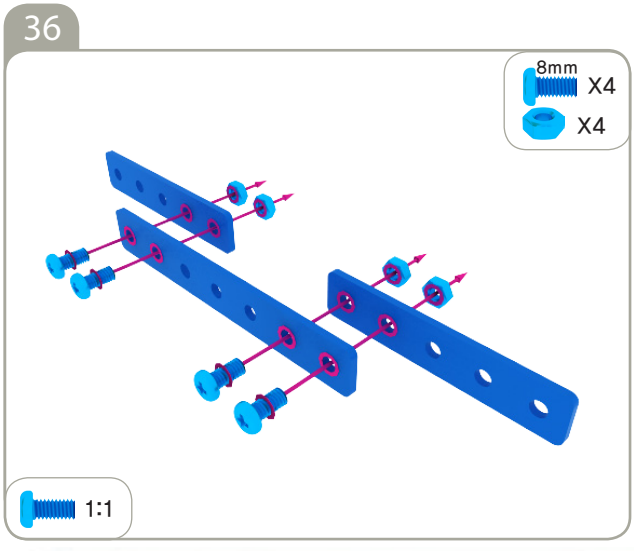

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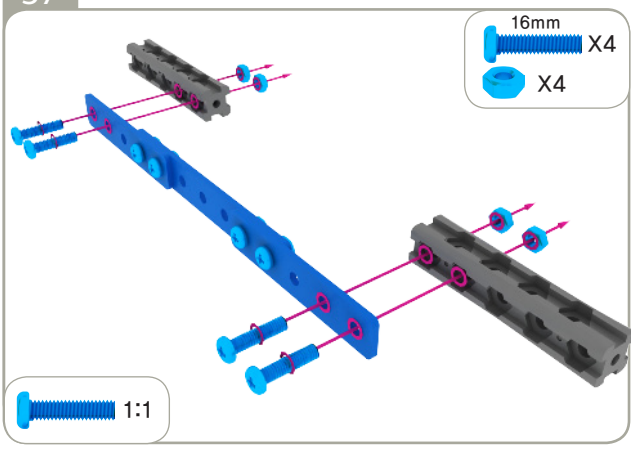

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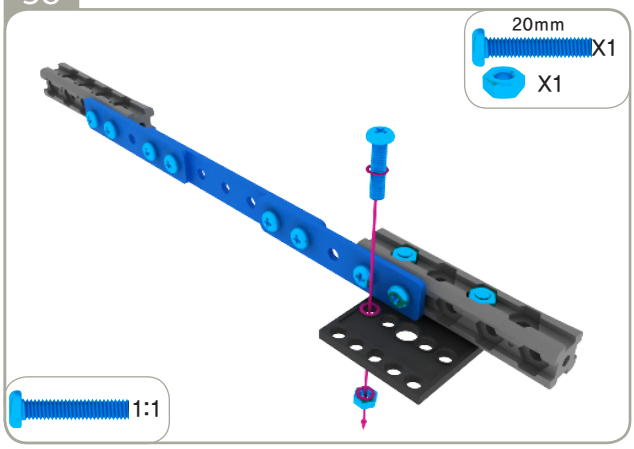

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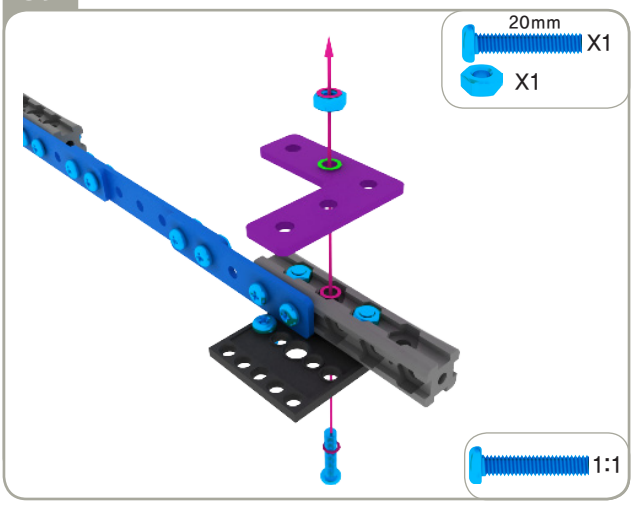

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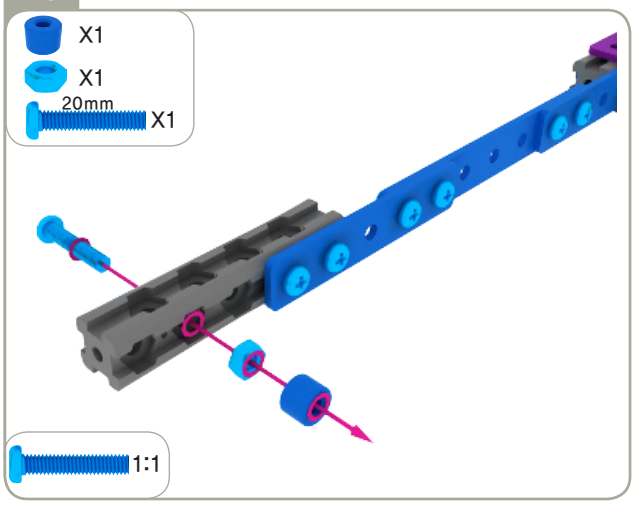

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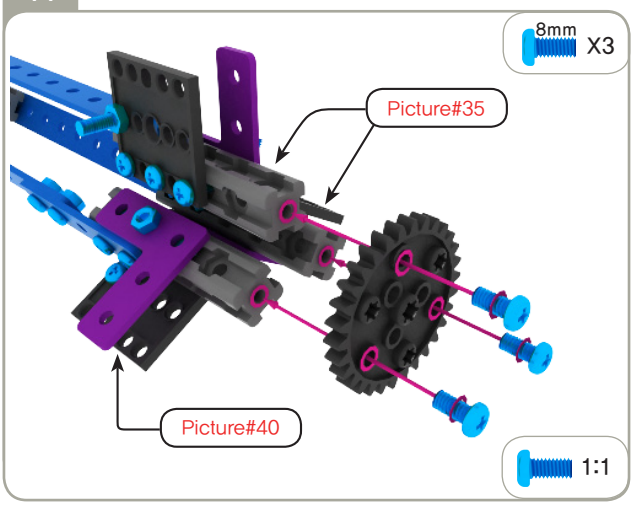

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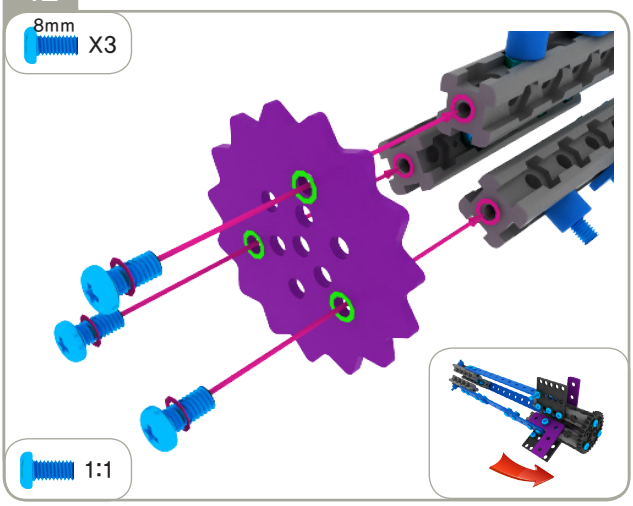

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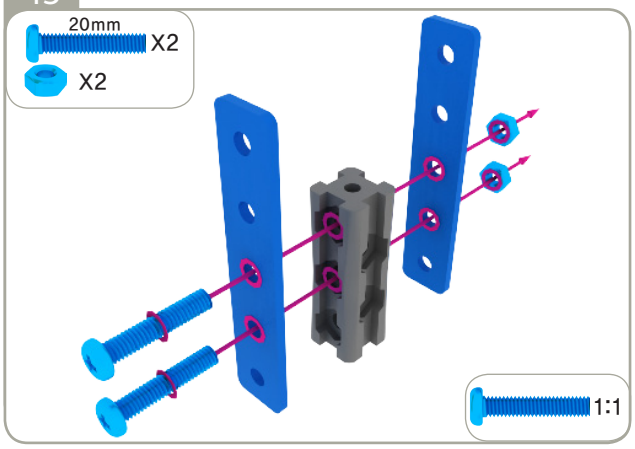

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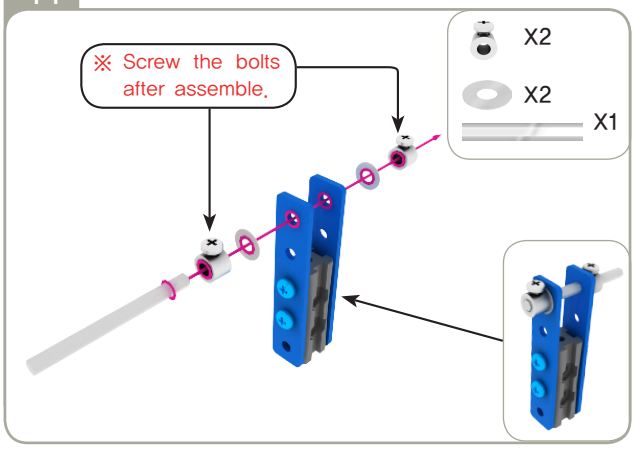

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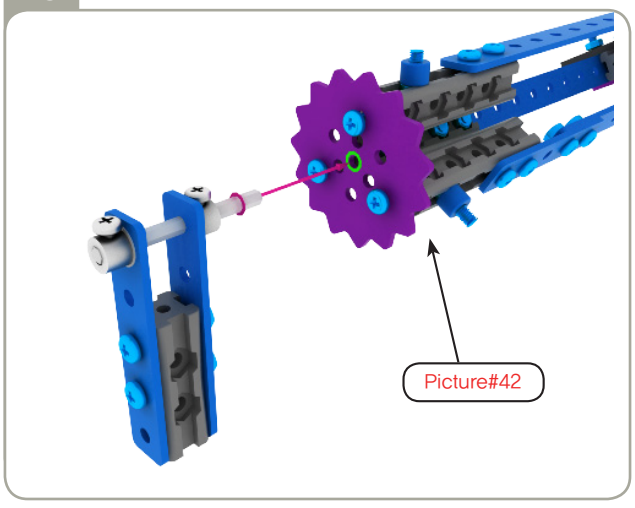

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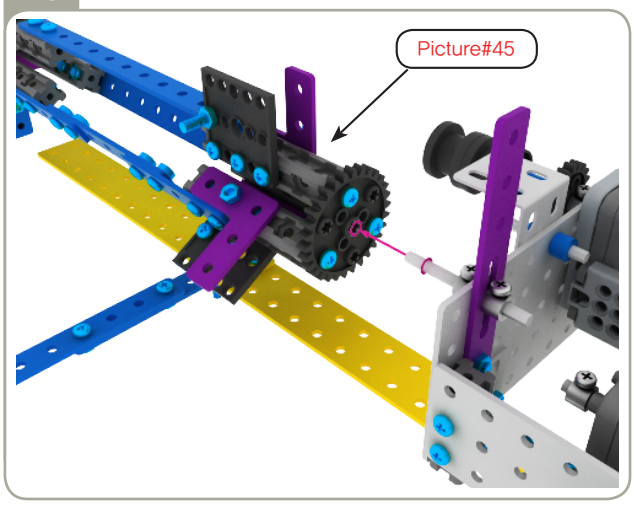

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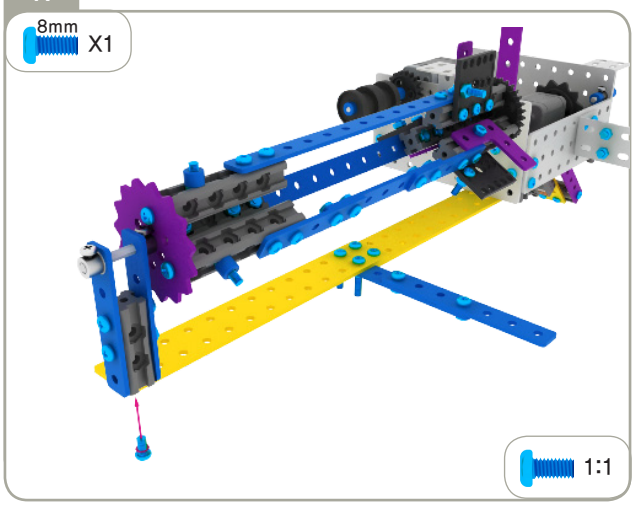

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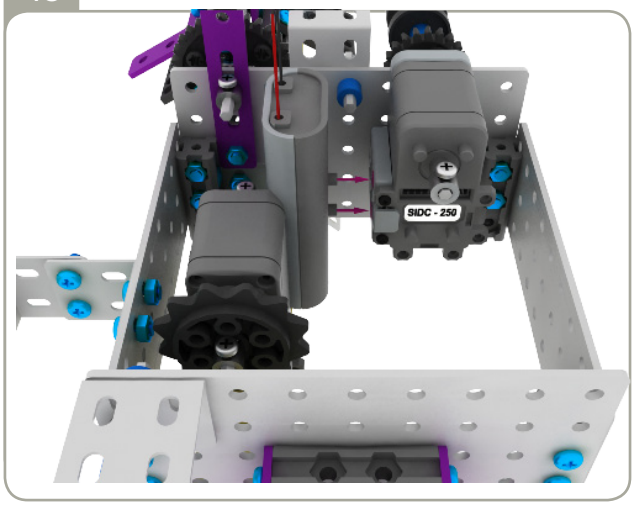

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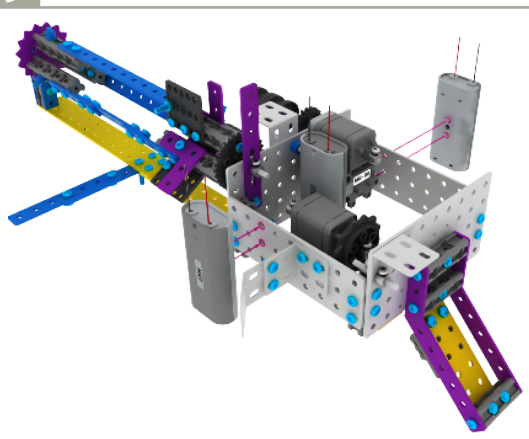
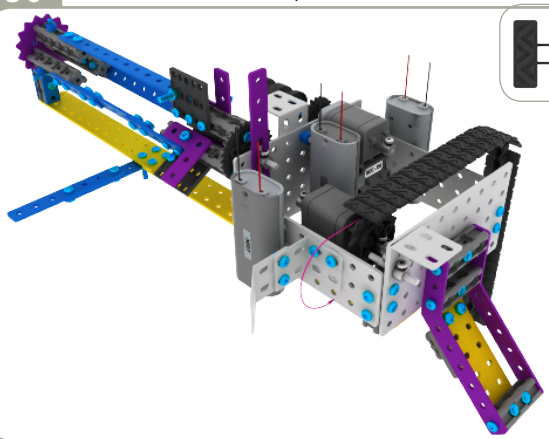


50 Assemble bullet clip



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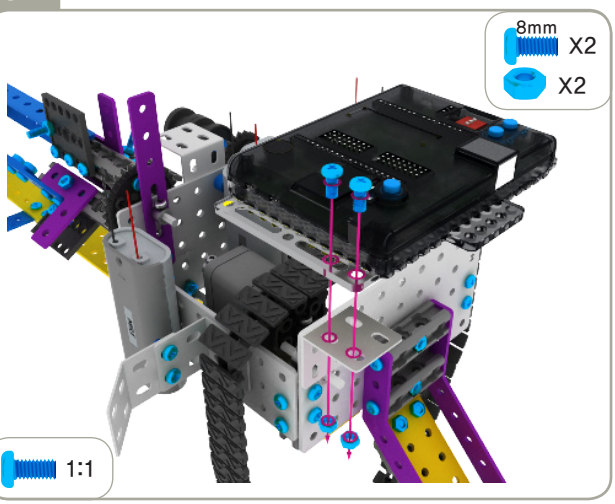
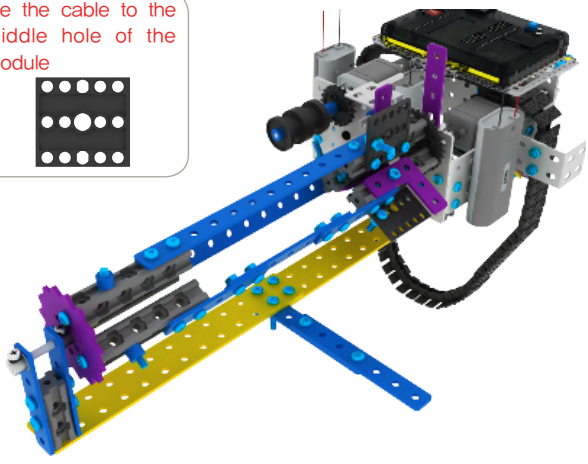
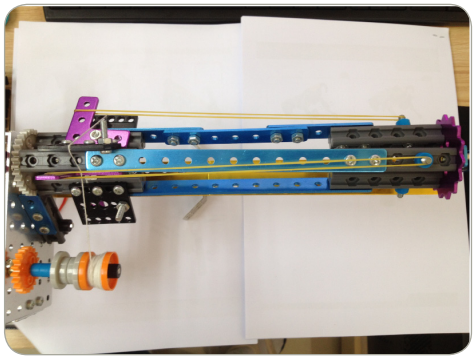
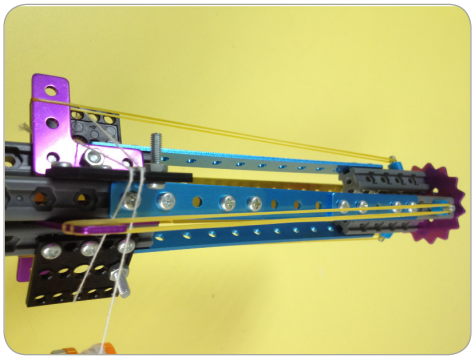


Complete

Tie the cable to the middle hole of the module

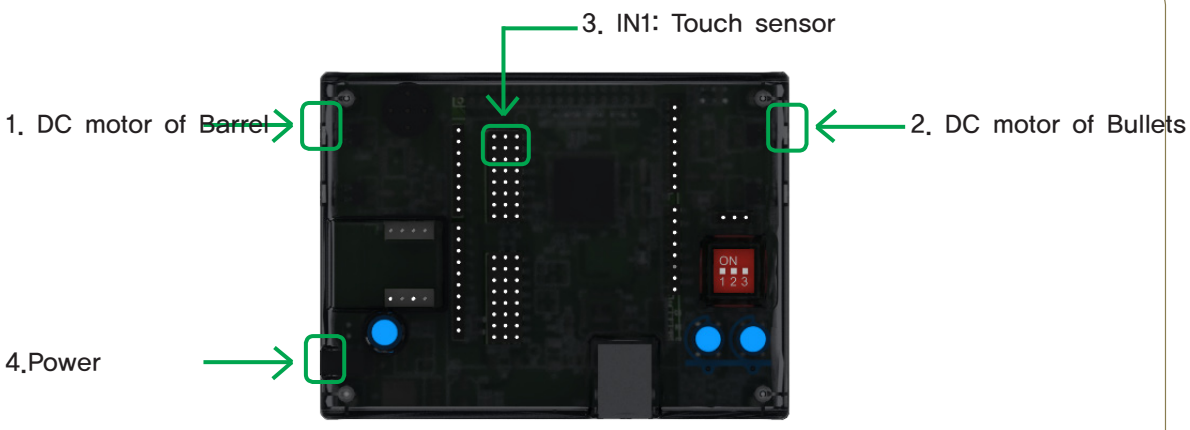






Wrapped around the cable as pictures, each filled with a rubber band wrapped around a cable.

Connecting the mainboard

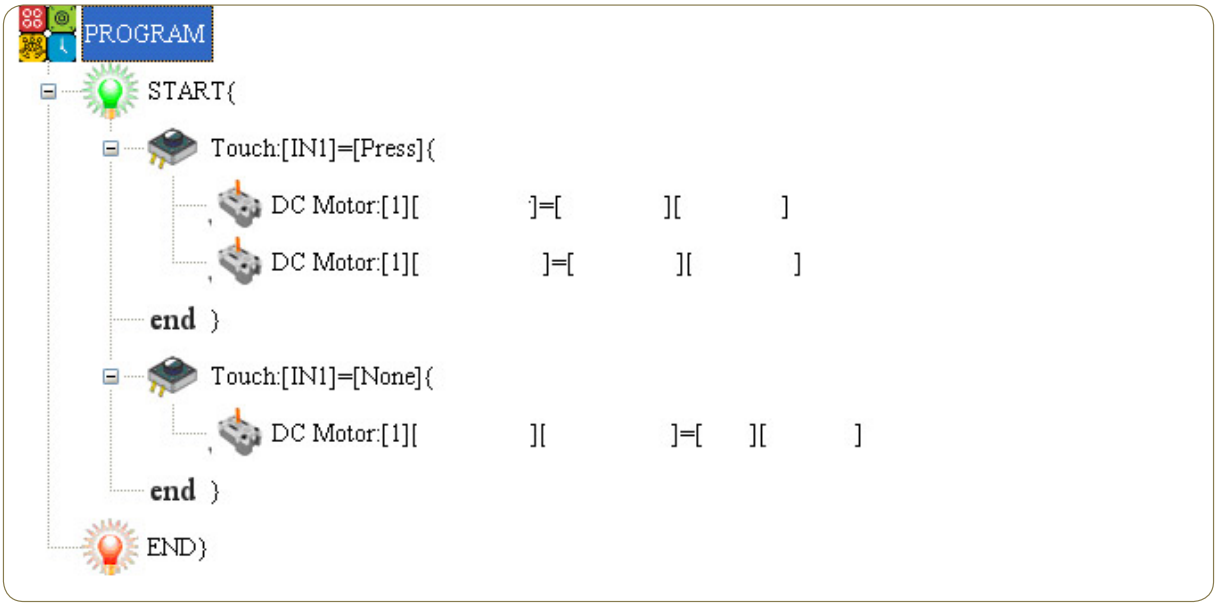


Connect in this order :

1. Connect the Barrel DC motor to L–MOTOR connector1.
2. Connect Bullet DC motor to R–MOTOR connector 2.
3. Connect Touch senor to INPUT connector.
4. Connect battery case to POWER connector.

Learn to compile program in advance

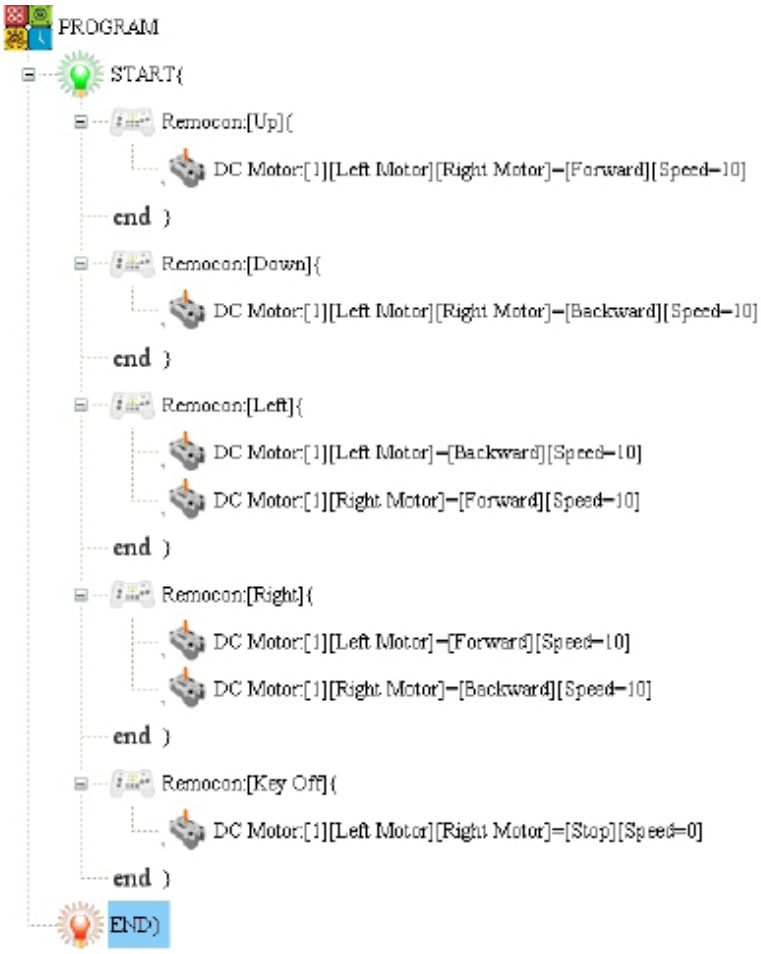
※ Try to write down the program before we compile on software.



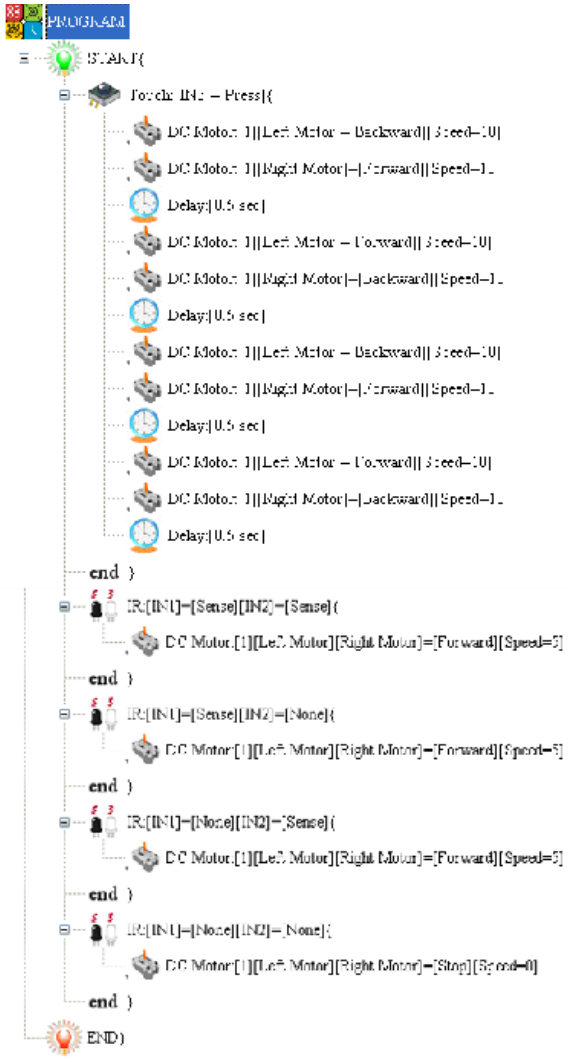
※ Program example : Refer to the back of book.

Program Example

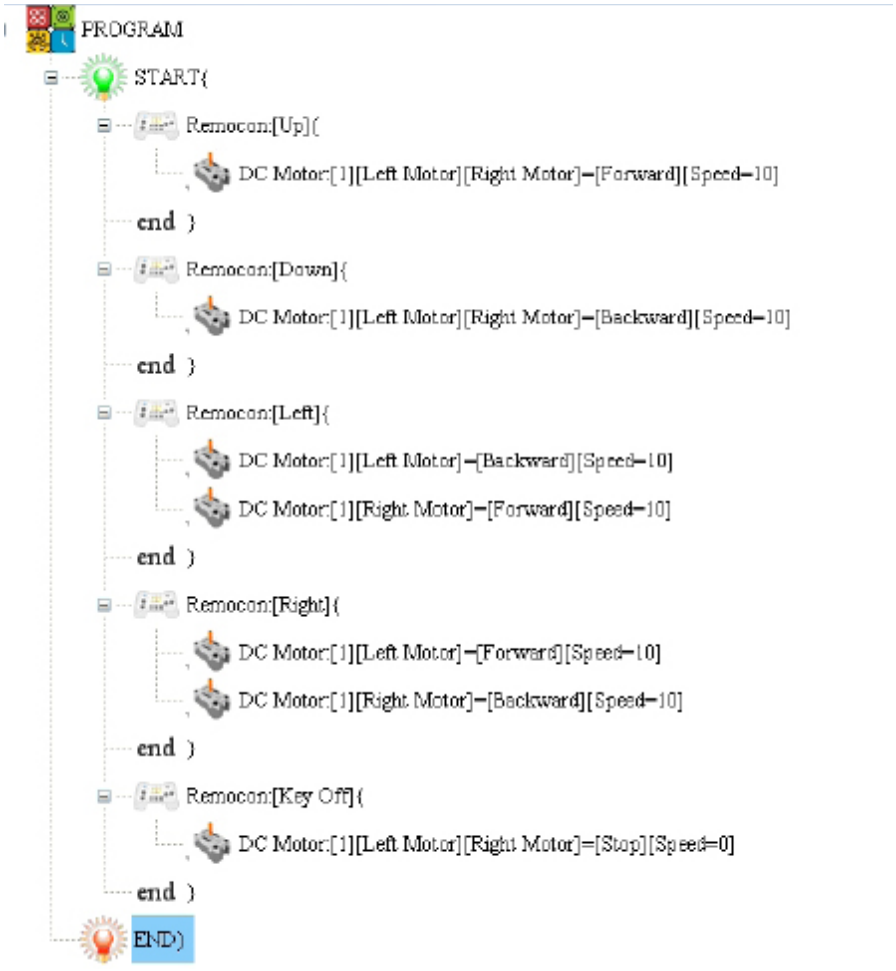
[BASIC TANK]



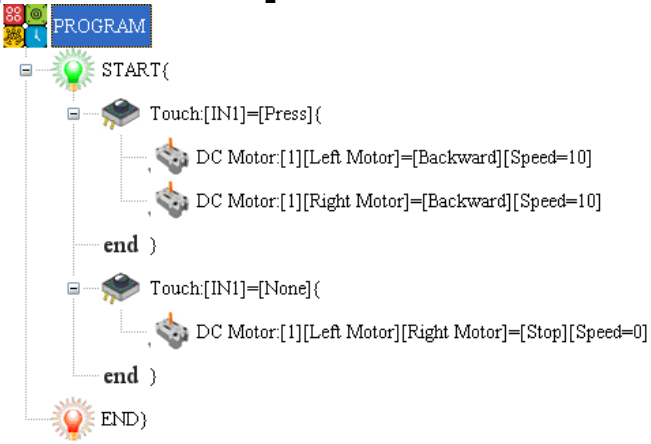
[DOG STALKER]


PROGRAM
START{
Touch: IN1 – Press|{
DC Motor: 1||Left Motor – Backward|| Speed=10|
DC Motor: 1||Right Motor|–|Forward|| Speed=1
Delay|0.5 sec|
DC Motor: 1||Left Motor – Forward|| Speed=10|
DC Motor: 1||Right Motor|–|Backward|| Speed=1
Delay|0.5 sec|
DC Motor: 1||Left Motor – Backward|| Speed=10|
DC Motor: 1||Right Motor|–|Forward|| Speed=1
Delay|0.5 sec|
DC Motor: 1||Left Motor – Forward|| Speed=10|
DC Motor: 1||Right Motor|–|Backward|| Speed=1
Delay|0.5 sec|
end }
IR:[IN1]=[Sense][IN2]=[Sense]{
DC Motor:[1][Left Motor][Right Motor]=[Forward][Speed=5]
end }
IR:[IN1]=[Sense][IN2]=[None]{
DC Motor:[1][Left Motor][Right Motor]=[Forward][Speed=5]
end }
IR:[IN1]=[None][IN2]=[Sense]{
DC Motor:[1][Left Motor][Right Motor]=[Forward][Speed=5]
end }
IR:[IN1]=[None][IN2]=[None]{
DC Motor:[1][Left Motor][Right Motor]=[Stop][Speed=0]
end }
END}

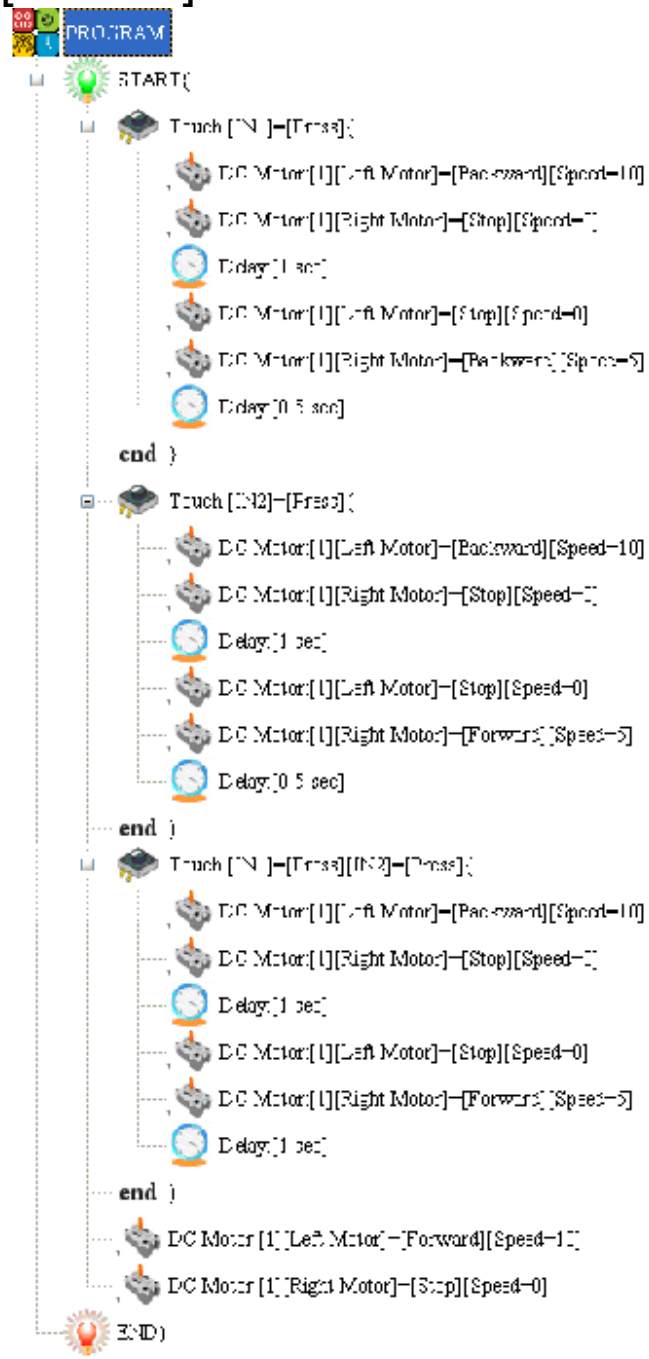
[BATTLE ROBOT]



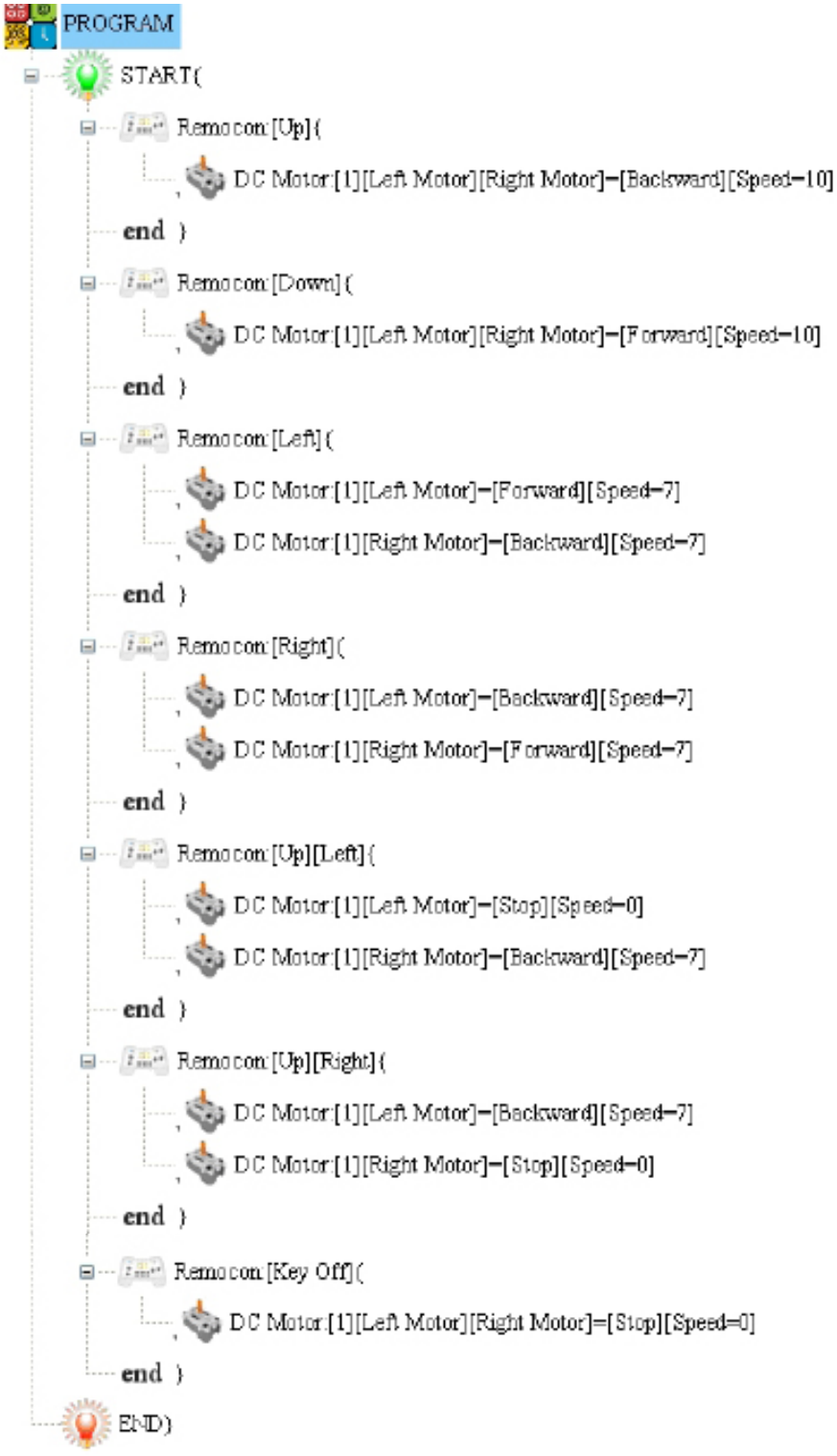
[TOUCH AVOIDER]



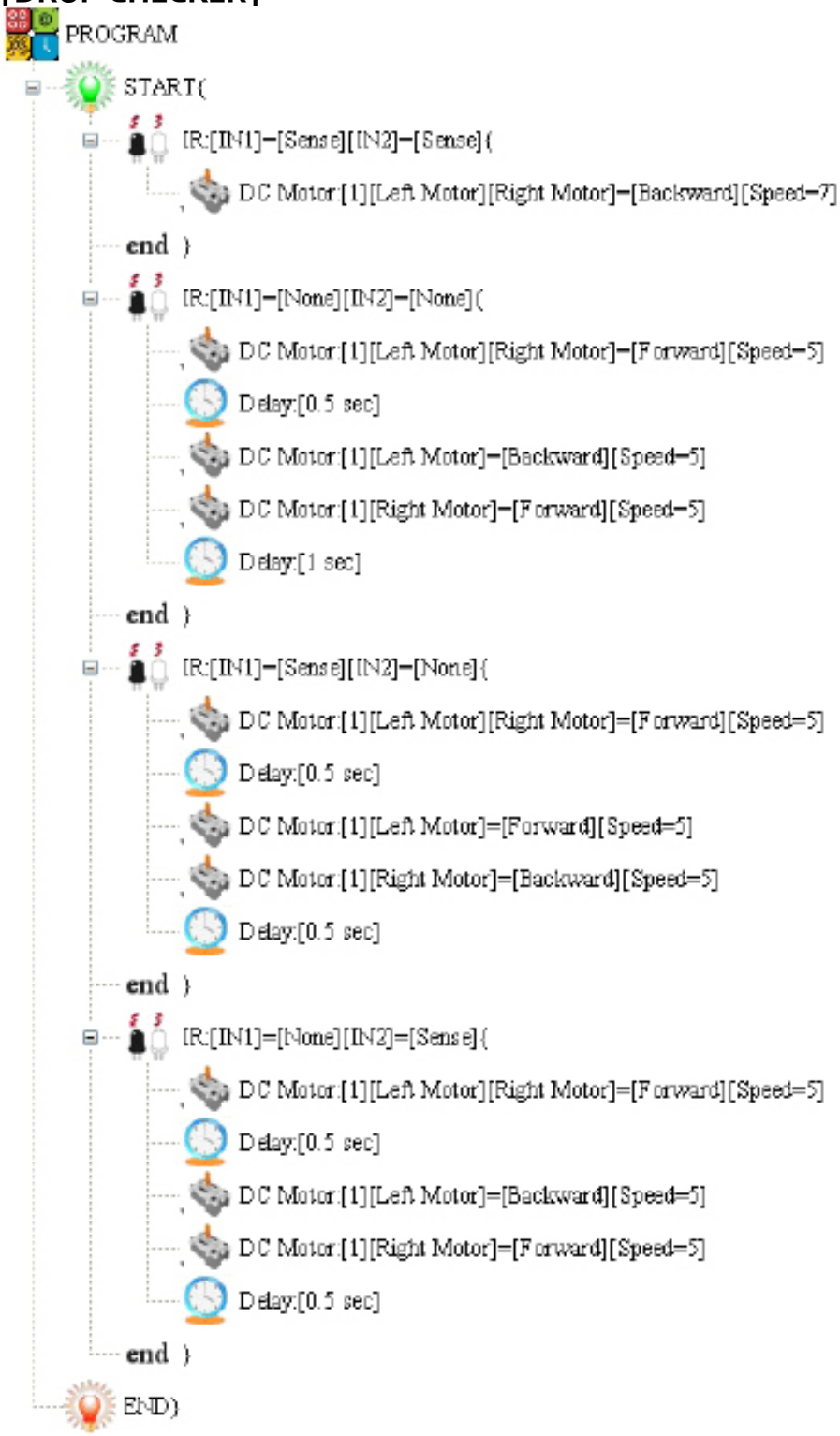
[FROG-BOT]


PROGRAM
START(
Touch [IN1]=[Press](
DC Motor[1][Left Motor]=[Backward][Speed=10]
DC Motor[1][Right Motor]=[Stop][Speed=]
Delay:[1 sec]
DC Motor[1][Left Motor]=[Stop][Speed=0]
DC Motor[1][Right Motor]=[Backward][Speed=5]
Delay:[0.5 sec]
end)
Touch [IN2]=[Press](
DC Motor[1][Left Motor]=[Backward][Speed=10]
DC Motor[1][Right Motor]=[Stop][Speed=]
Delay:[1 sec]
DC Motor[1][Left Motor]=[Stop][Speed=0]
DC Motor[1][Right Motor]=[Forward][Speed=5]
Delay:[0.5 sec]
end)
Touch [IN1]=[Press][IN2]=[Press](
DC Motor[1][Left Motor]=[Backward][Speed=10]
DC Motor[1][Right Motor]=[Stop][Speed=]
Delay:[1 sec]
DC Motor[1][Left Motor]=[Stop][Speed=0]
DC Motor[1][Right Motor]=[Forward][Speed=5]
Delay:[1 sec]
end)
DC Motor [1] [Left Motor]=[Forward][Speed=1]
DC Motor [1] [Right Motor]=[Stop][Speed=0]
END)

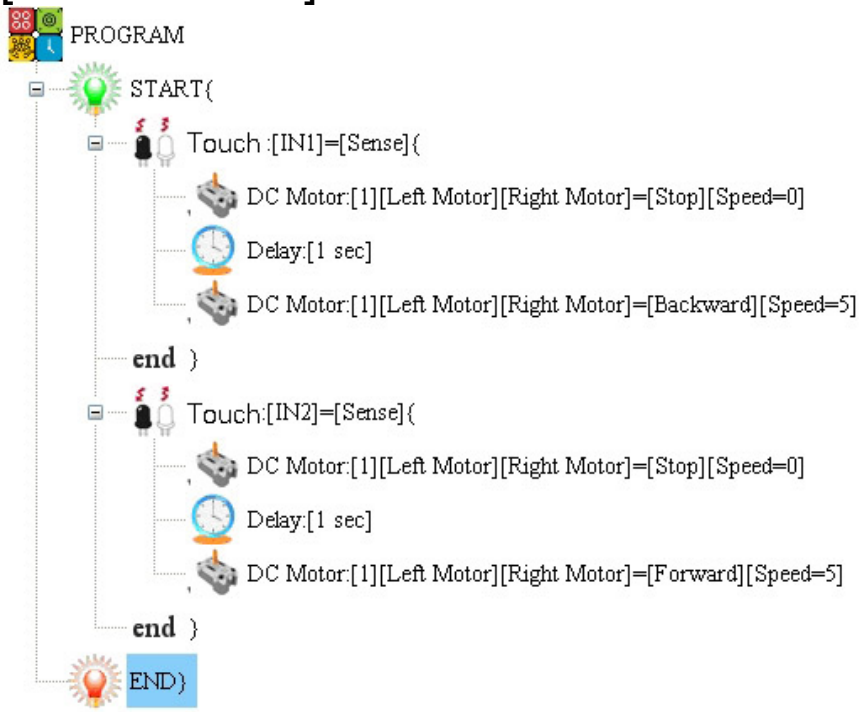
[SOCCER ROBOT]



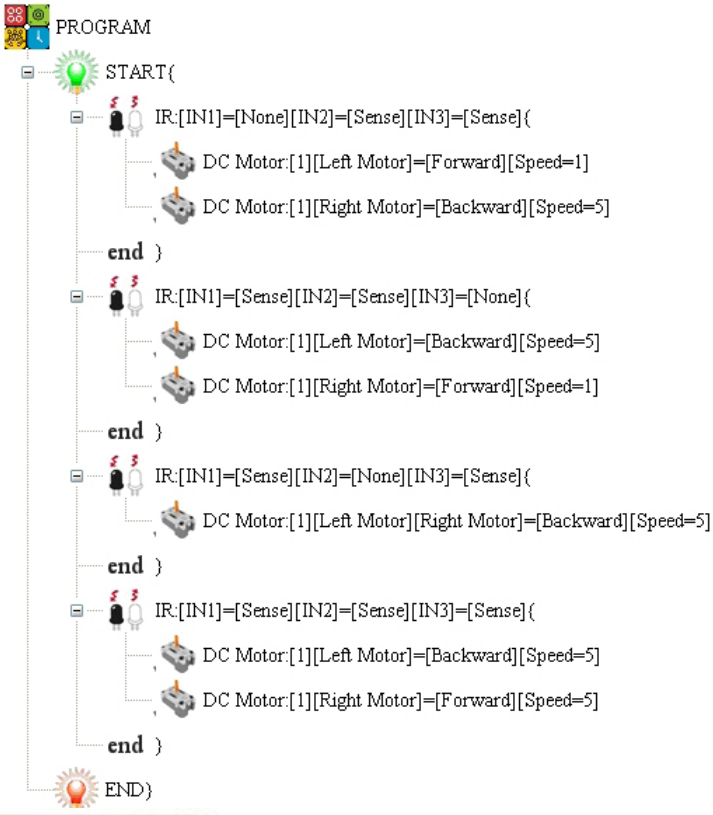
[DROP CHECKER]



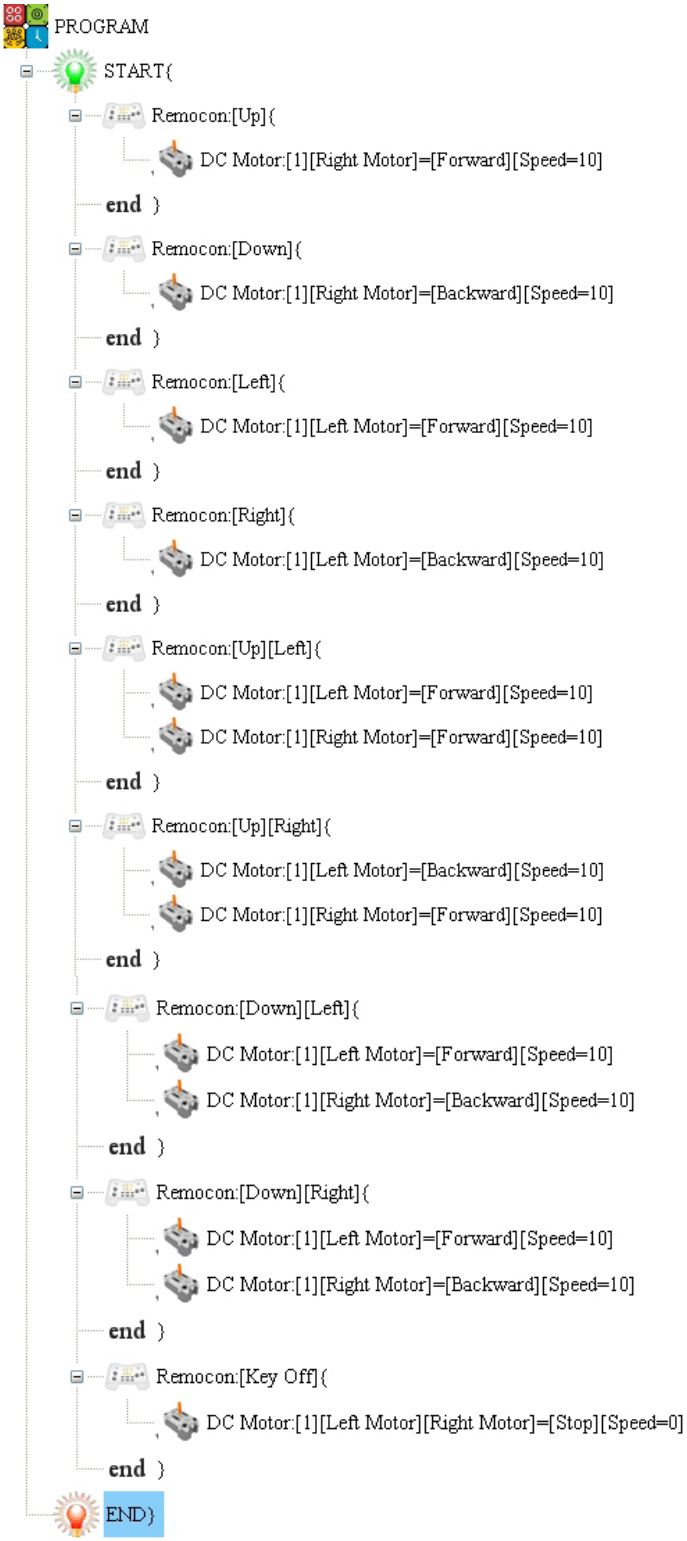
[SHUTTLE CARRIER]



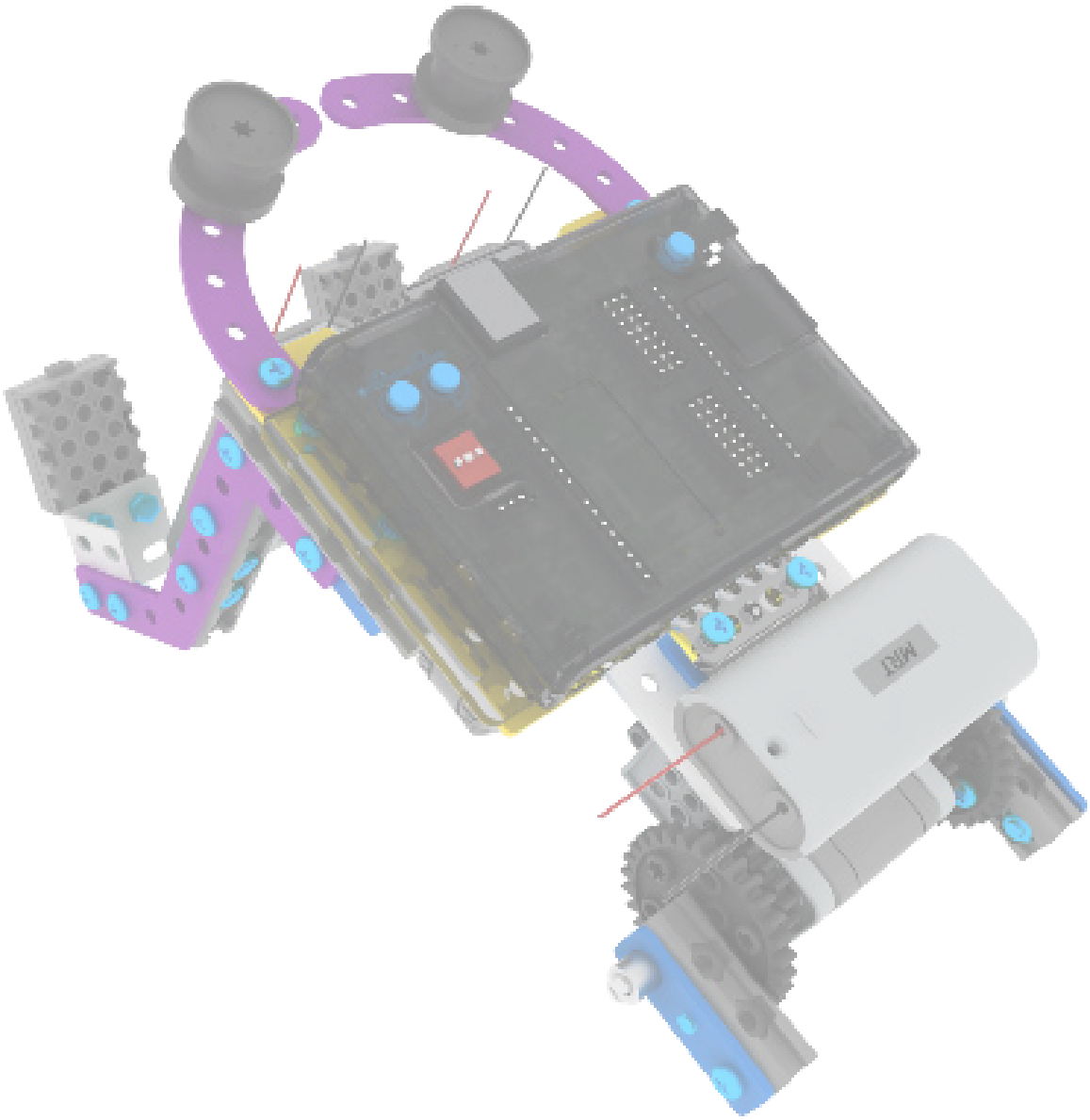
[TRACING TANK]



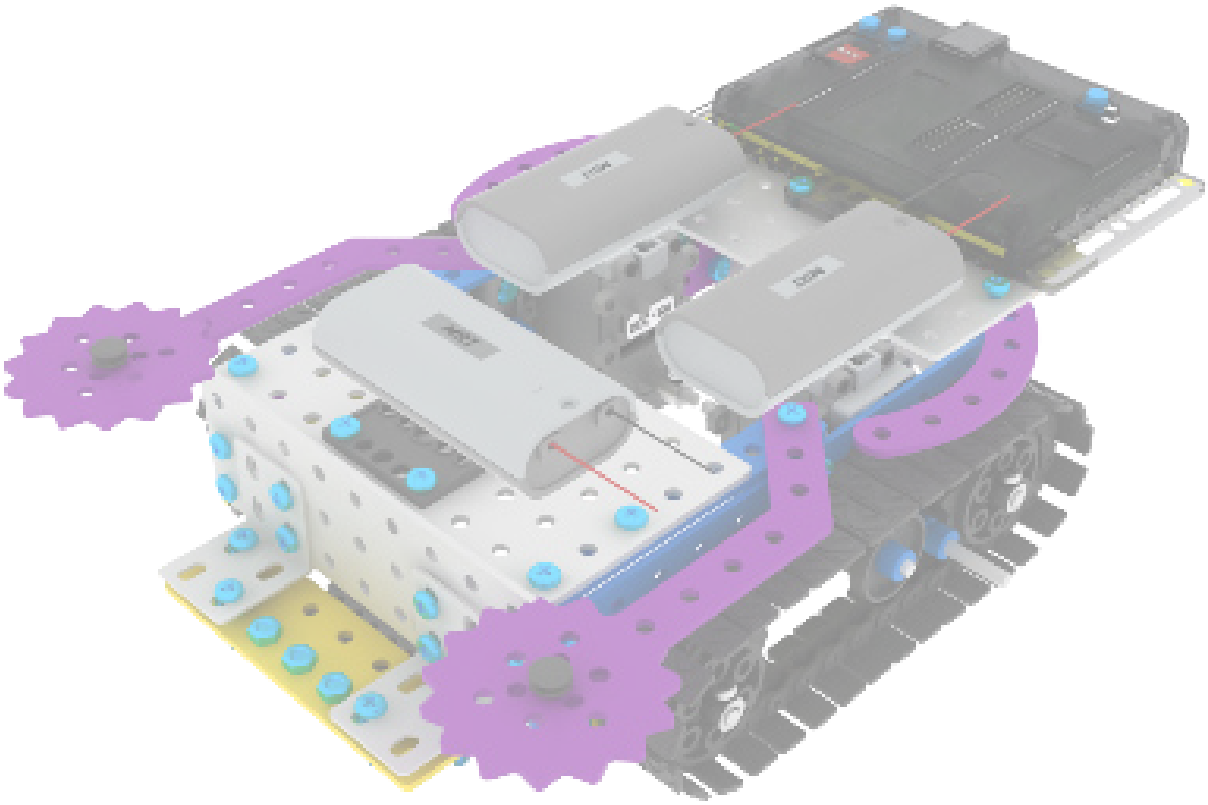
[CLASSIC CAR]


PROGRAM
START{
Remocon:[Up]{
DC Motor:[1][Right Motor]=[Forward][Speed=10]
end }
Remocon:[Down]{
DC Motor:[1][Right Motor]=[Backward][Speed=10]
end }
Remocon:[Left]{
DC Motor:[1][Left Motor]=[Forward][Speed=10]
end }
Remocon:[Right]{
DC Motor:[1][Left Motor]=[Backward][Speed=10]
end }
Remocon:[Up][Left]{
DC Motor:[1][Left Motor]=[Forward][Speed=10]
DC Motor:[1][Right Motor]=[Forward][Speed=10]
end }
Remocon:[Up][Right]{
DC Motor:[1][Left Motor]=[Backward][Speed=10]
DC Motor:[1][Right Motor]=[Forward][Speed=10]
end }
Remocon:[Down][Left]{
DC Motor:[1][Left Motor]=[Forward][Speed=10]
DC Motor:[1][Right Motor]=[Backward][Speed=10]
end }
Remocon:[Down][Right]{
DC Motor:[1][Left Motor]=[Forward][Speed=10]
DC Motor:[1][Right Motor]=[Backward][Speed=10]
end }
Remocon:[Key Off]{
DC Motor:[1][Left Motor][Right Motor]=[Stop][Speed=0]
end }
END}

MEMO



MEMO



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