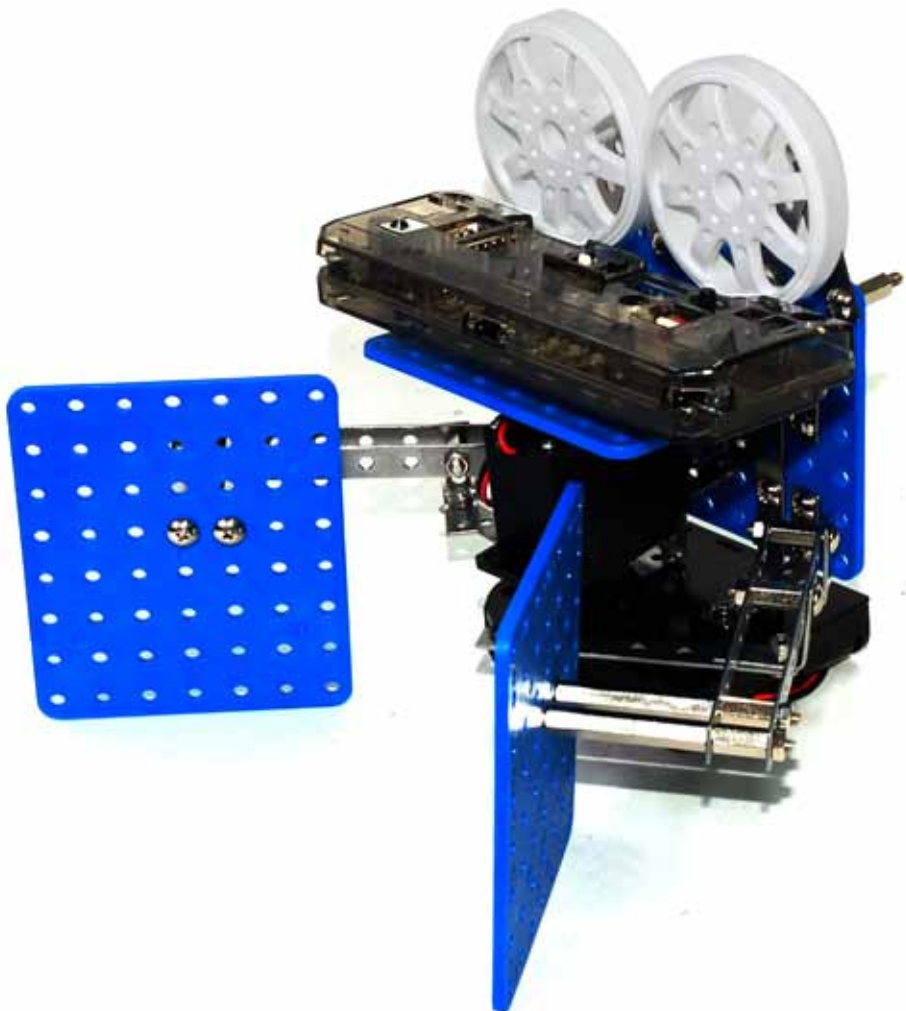


9. 쌀보리 로봇 (Motion Capturing Robot)



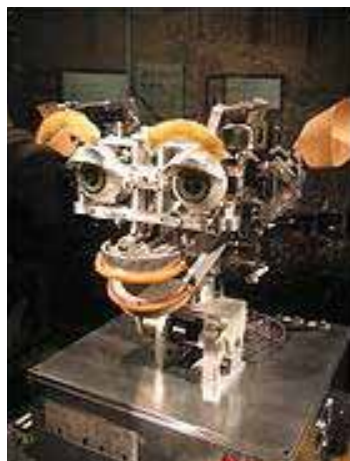
소개 및 동작원리

– Introduction & working principle

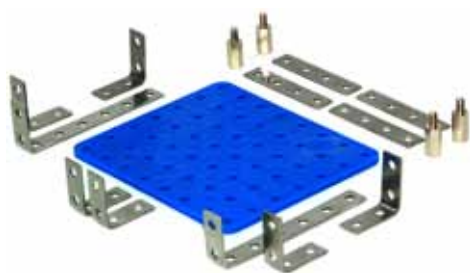


로봇의 몸체로 들어오는 물체(사람의 손)를 감지하여 집게를 오므려서 물체를 잡는 로봇입니다. 이 때 물체가 감지될 때마다 무조건 잡는 것이 아니라 어떤 경우는 물체를 잡기도 하고 어떤 경우는 잡지 않음으로 쌀보리 게임을 가능하게 합니다.

이처럼 로봇의 기능 중에는 무작위(random)로 동작이 일어나야 하는 경우가 있으며 특히 전자게임기와 같은 엔터테인먼트(entertainment)형 기기에 자주 활용됩니다.



1



X 20



X 20



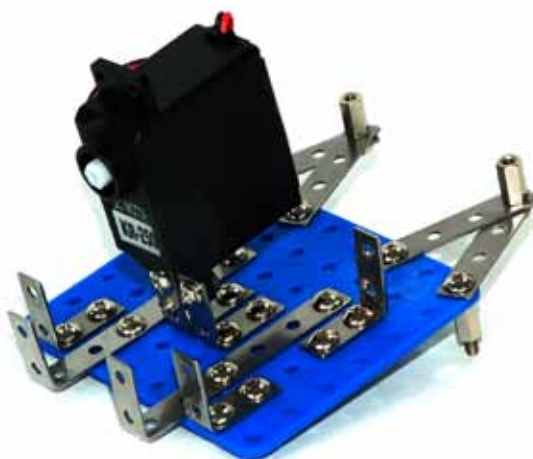
2



X 2



X 2



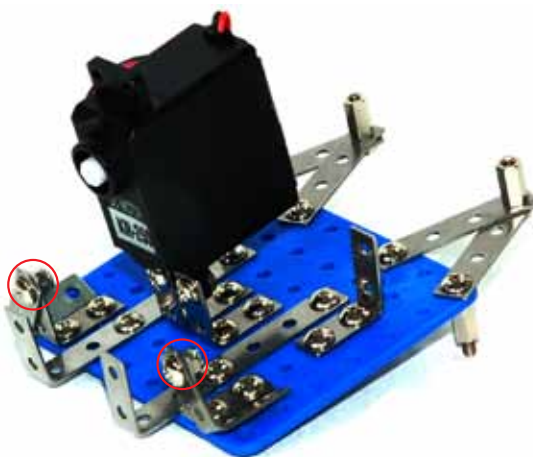
3



X 2



X 2



4



X 2



X 4



X 2

5



X 1

6

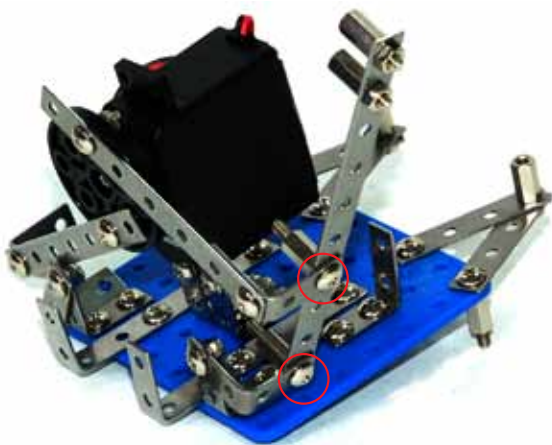


X 2

7



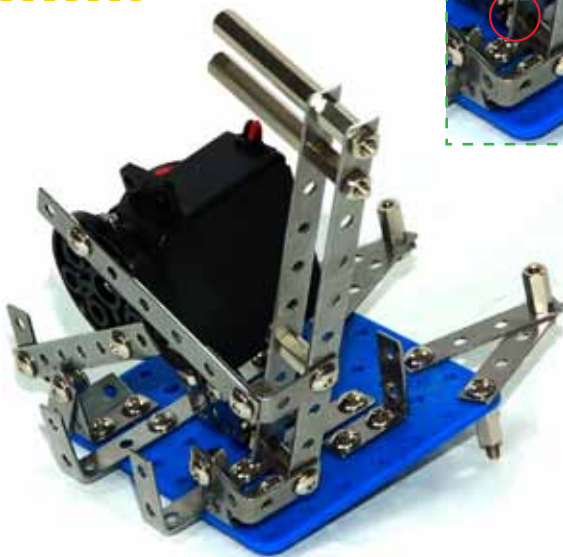
X 2



8



X 2



9

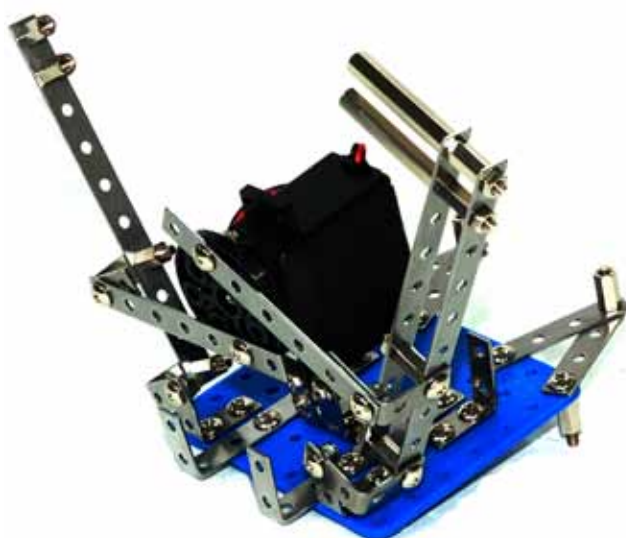
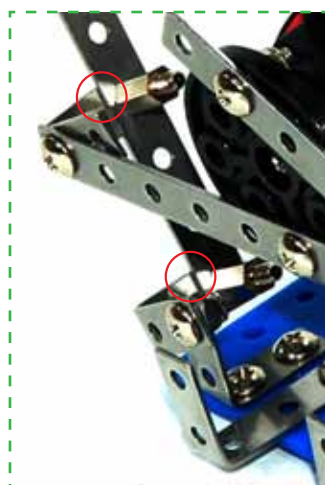


X 2

10



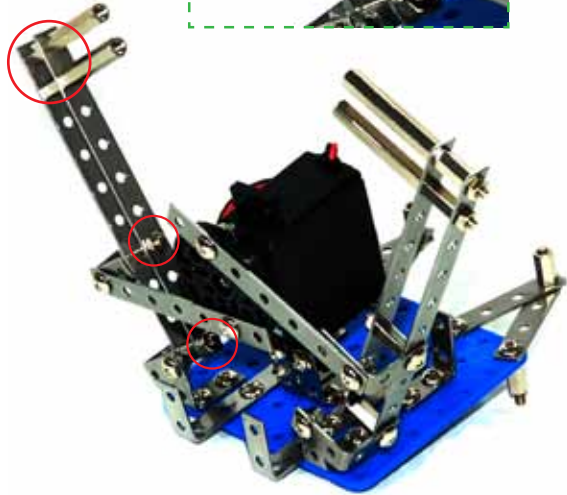
X 2



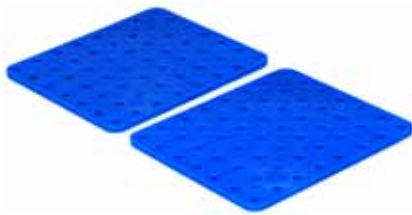
11



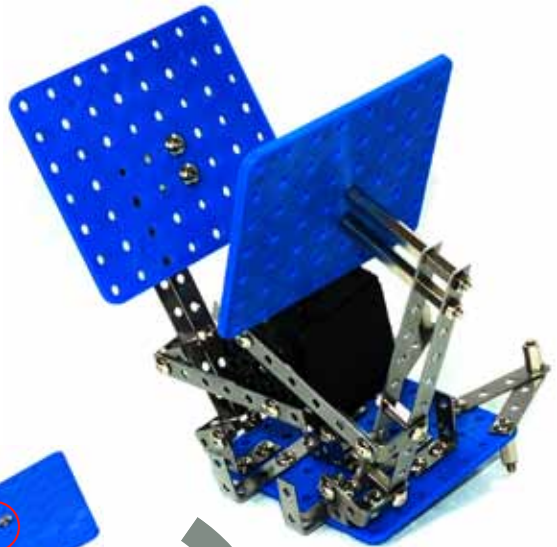
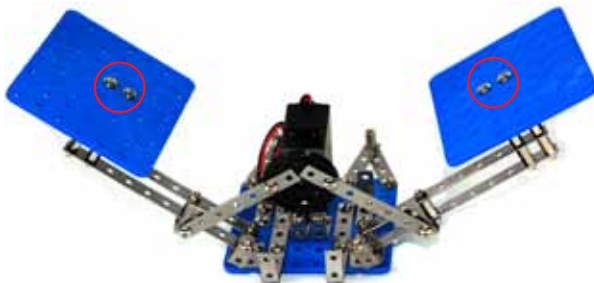
X 2



12



X 4



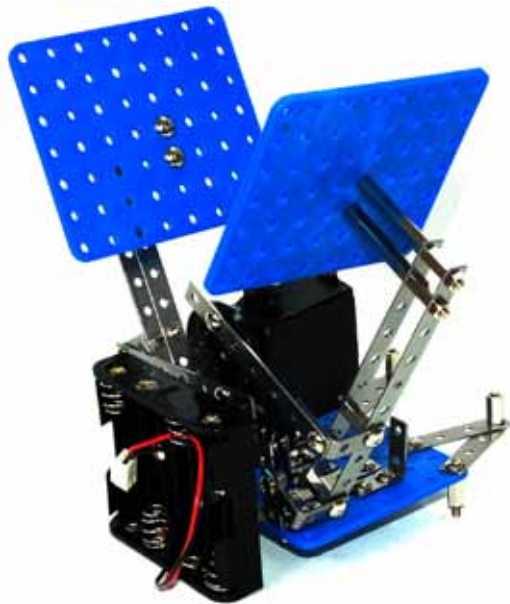
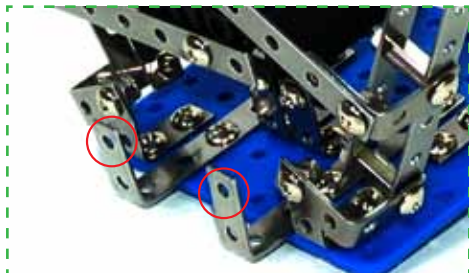
13



X 2



X 2



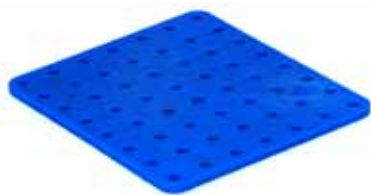
14



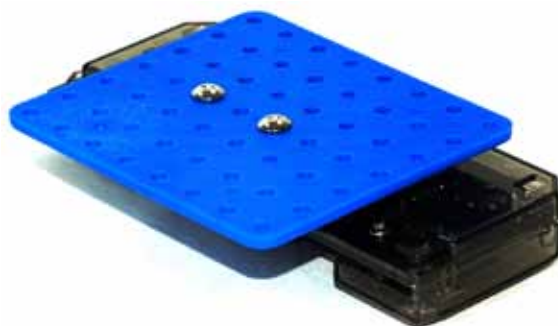
X 2



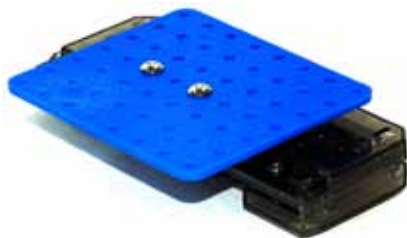
15



X 2



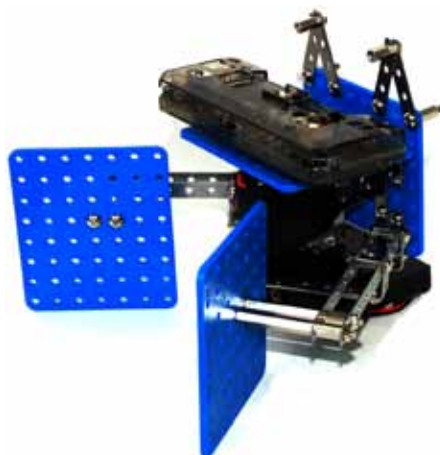
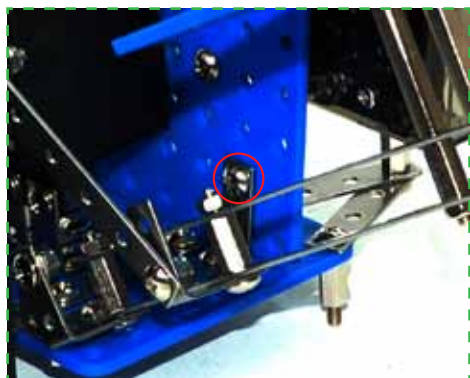
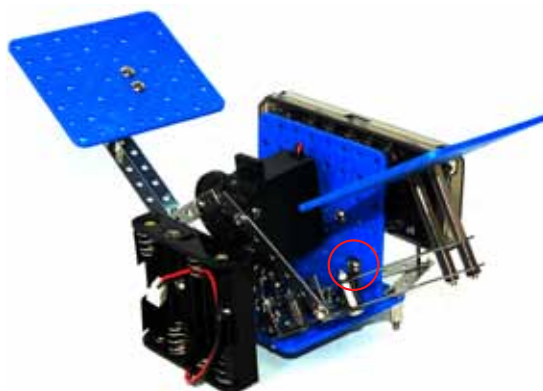
16

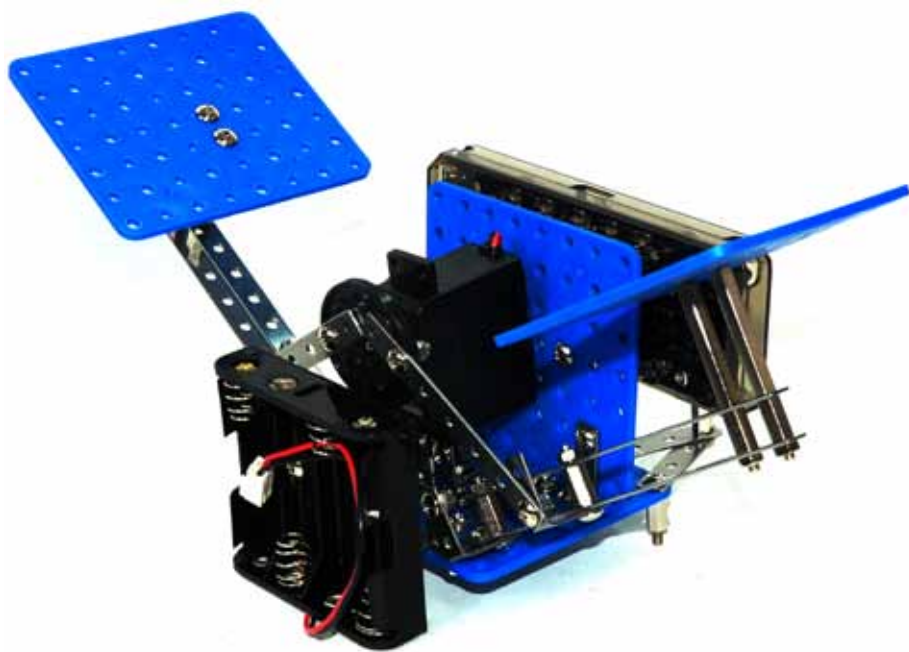
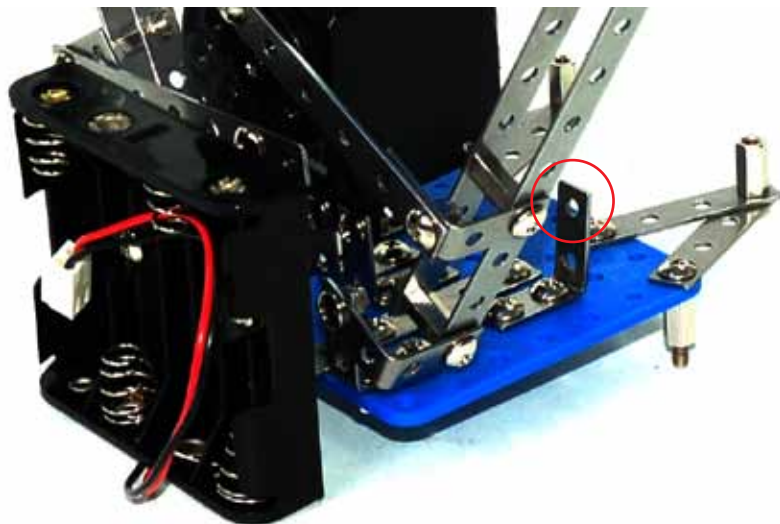


X 2



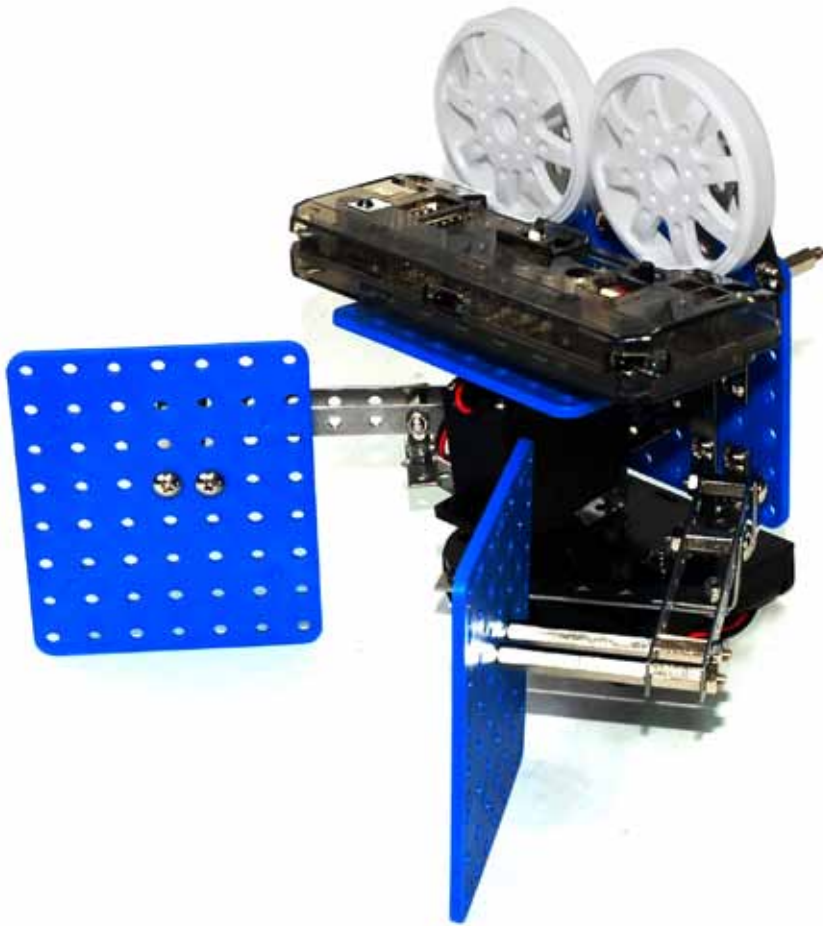
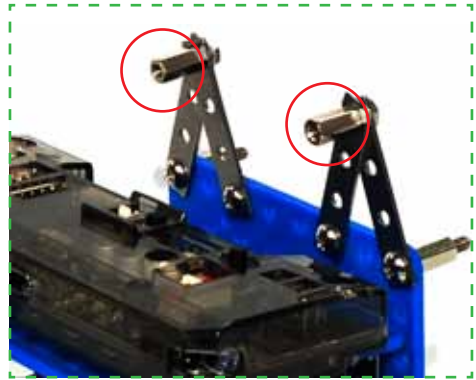
X 2



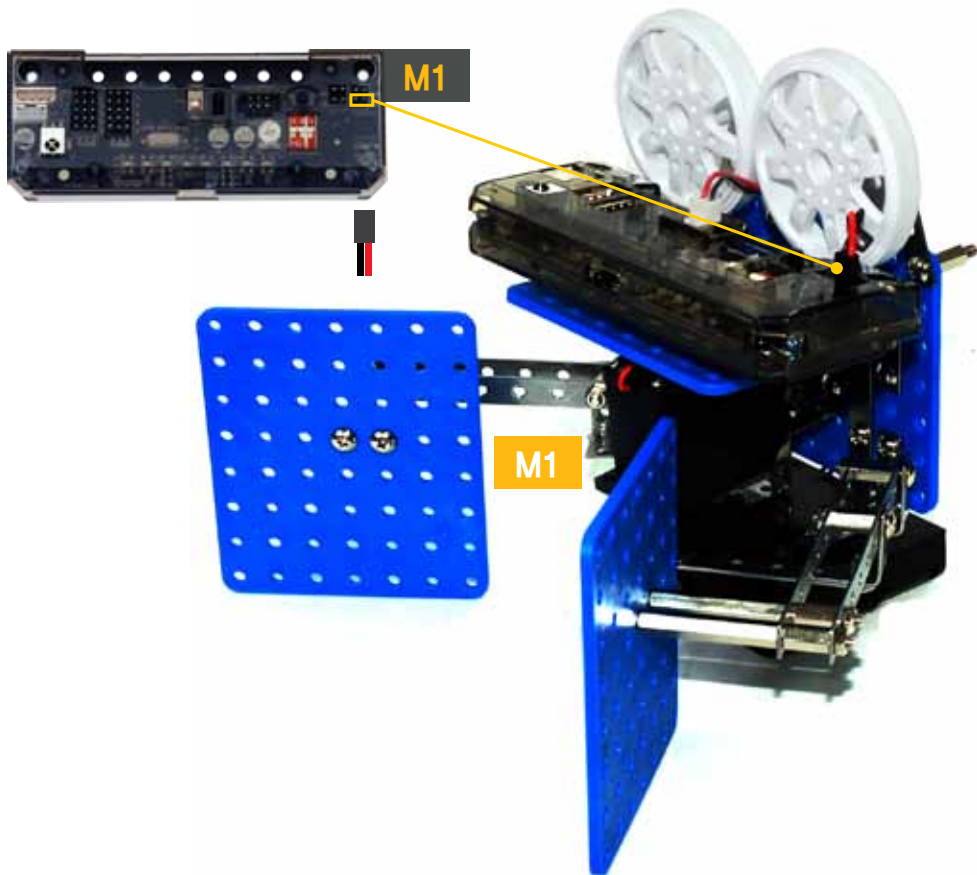




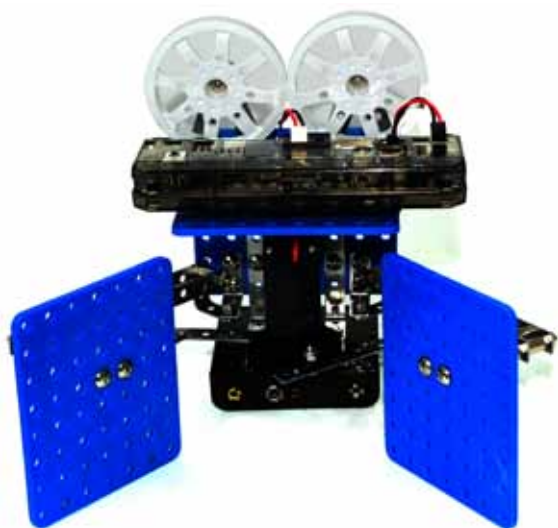
X 2



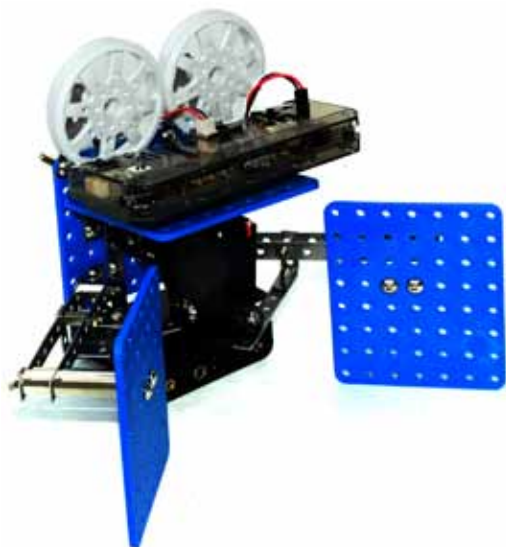
완성



정면



우

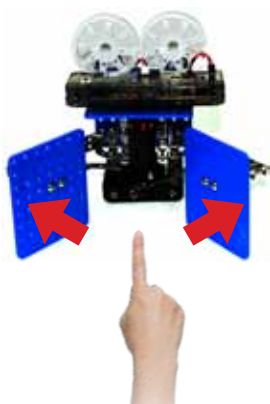


구동하기



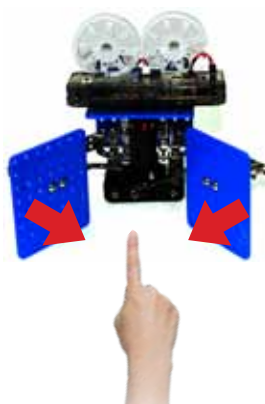
쌀보리 로봇은 프로그램 모드 9번을 선택하여 구동합니다.

Before

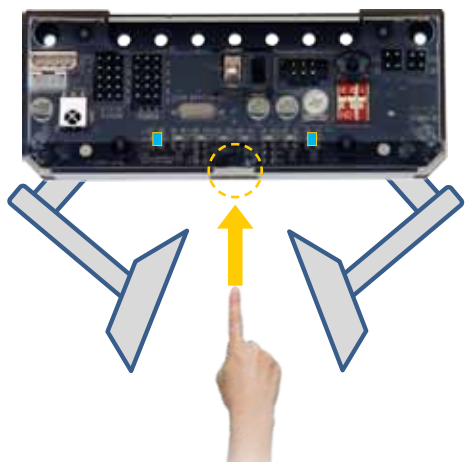


손을 로봇의 팔 사이로 가져갑니다.

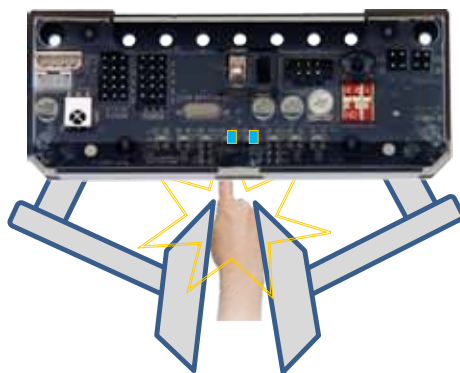
After



로봇의 중앙센서까지 손을 가까이 둡니다.



로봇이 팔을 벌린 상태로 대기합니다.



로봇의 중앙센서가 물체를 인식하여 손을 잡습니다.