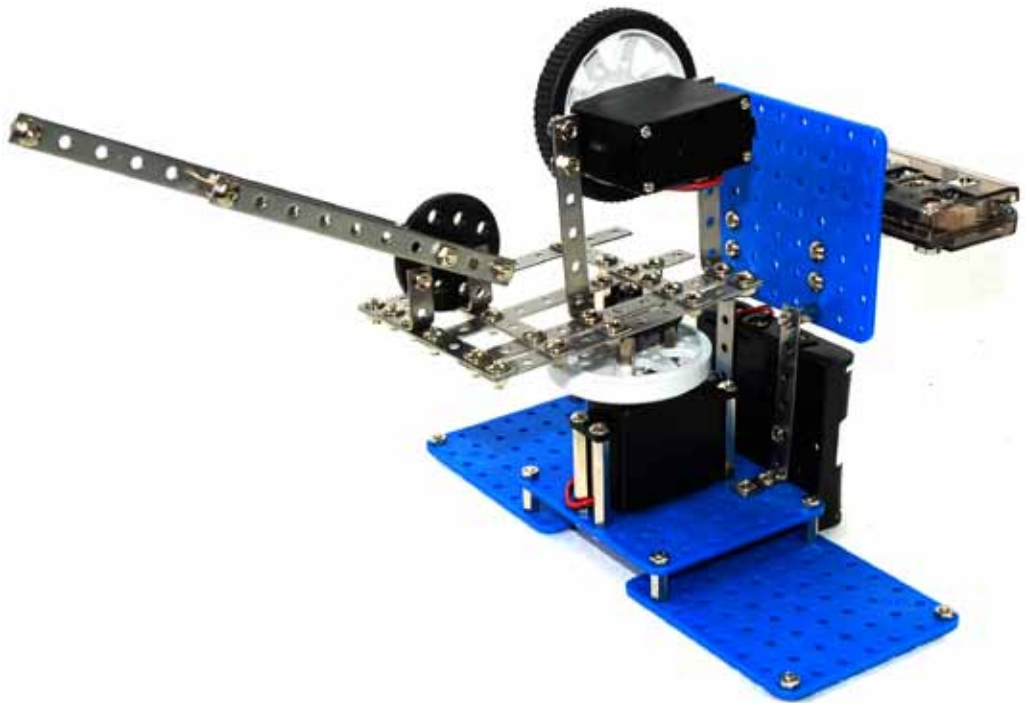


8. 터렛 로봇 (Turret Robot)

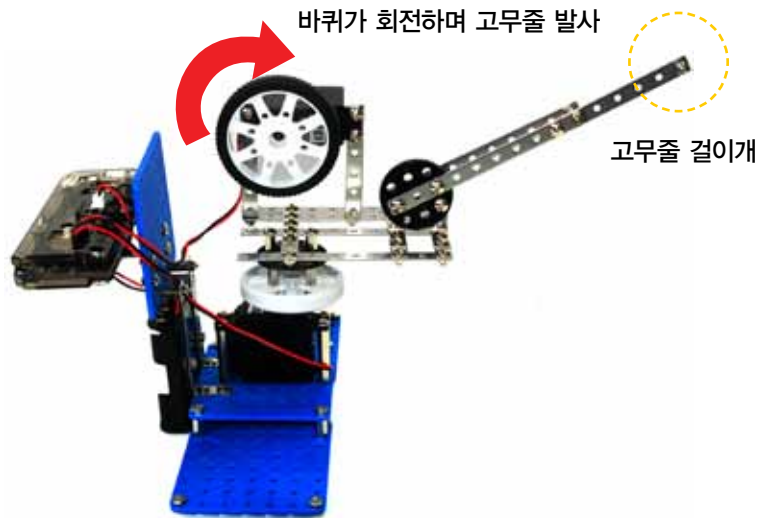


소개 및 동작원리

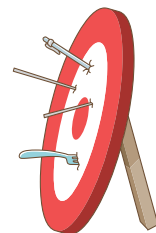
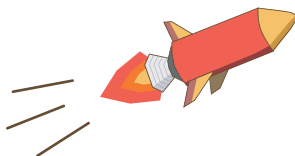
– Introduction & working principle



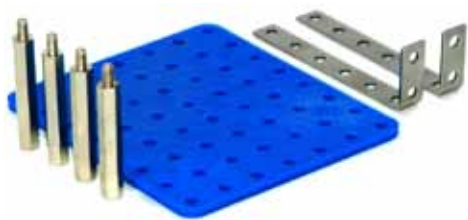
고무줄을 포탑 상단의 바퀴와 포신 끝단 사이에 걸어서 장력을 발생시키고, 1개의 DC모터를 사용해 로봇 상단의 포탑을 회전시켜 과녁에 겨냥할 수 있도록 합니다.



고무줄이 걸려 있는 포탑의 바퀴를 포신 방향으로 회전 시키면 고무줄이 발사 되는데 이 때 고무줄의 운동량은 바퀴의 회전속도에 비례해 증가하므로 바퀴의 회전 속도를 조절하면 고무줄의 발사 거리도 조절할 수 있습니다.



1



X 4



X 8



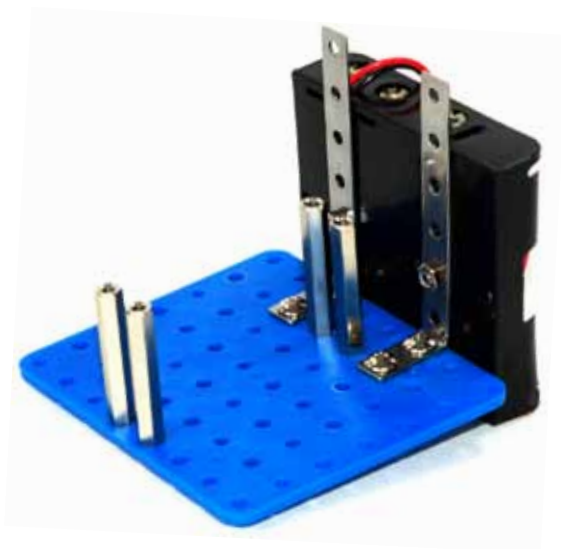
2



X 2



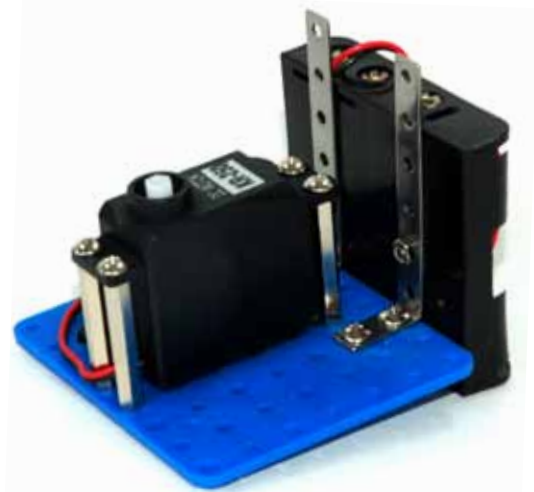
X 2



3



X 4



4



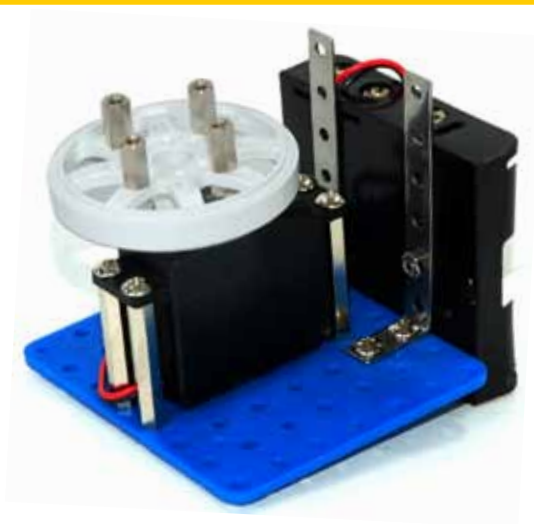
X 4



5



X 1

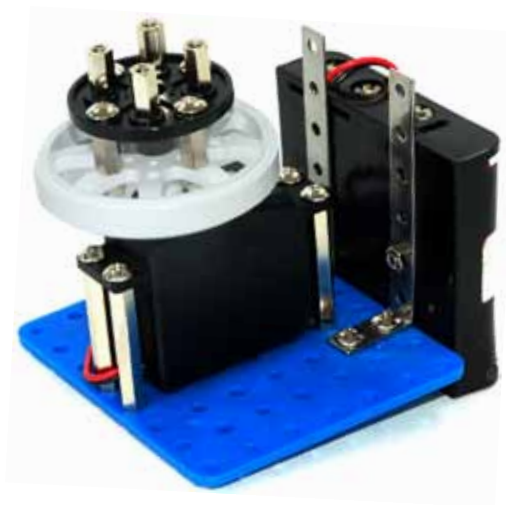


6



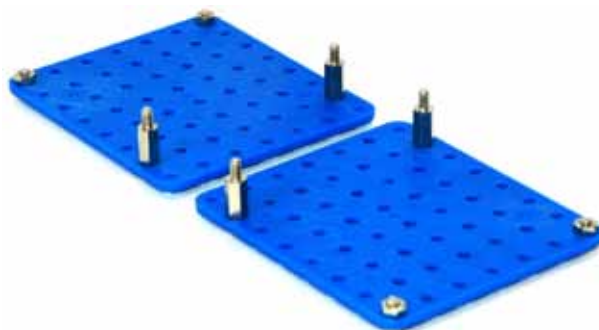
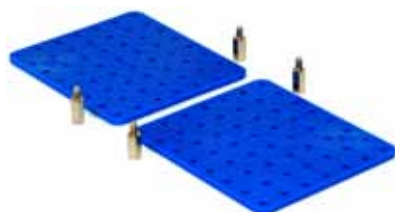
X 4

7



X 4

8

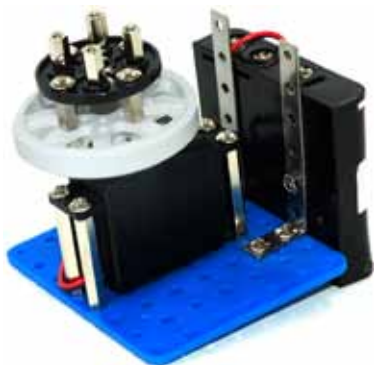


X 8

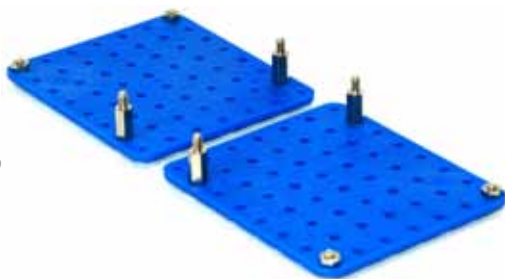


X 4

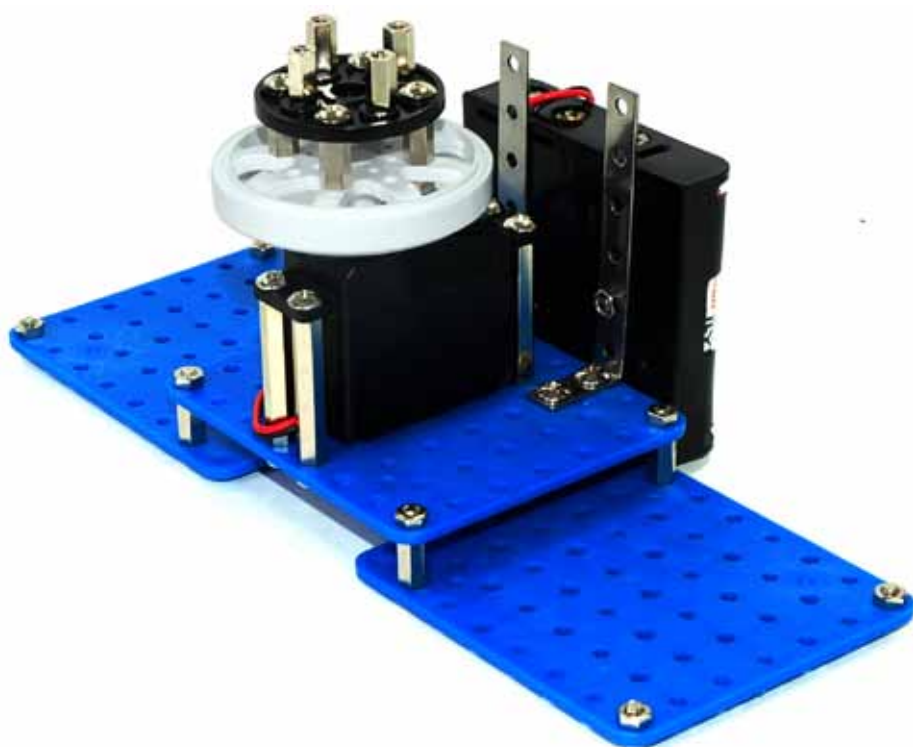
9



+



X 4

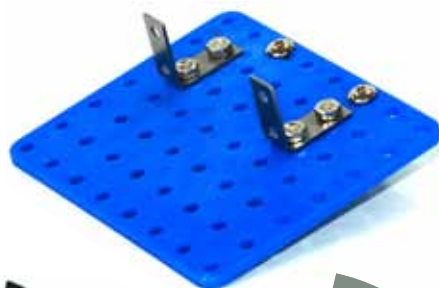
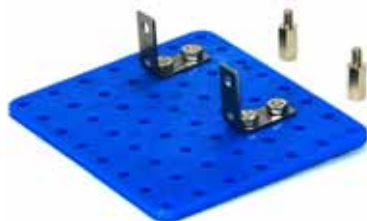


10



 X 4  X 4

11



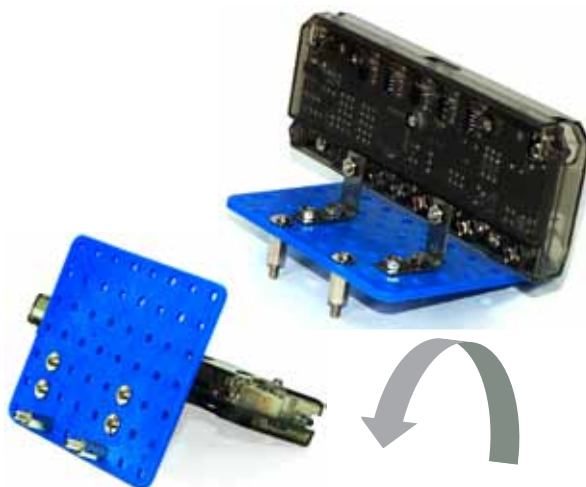
 X 2

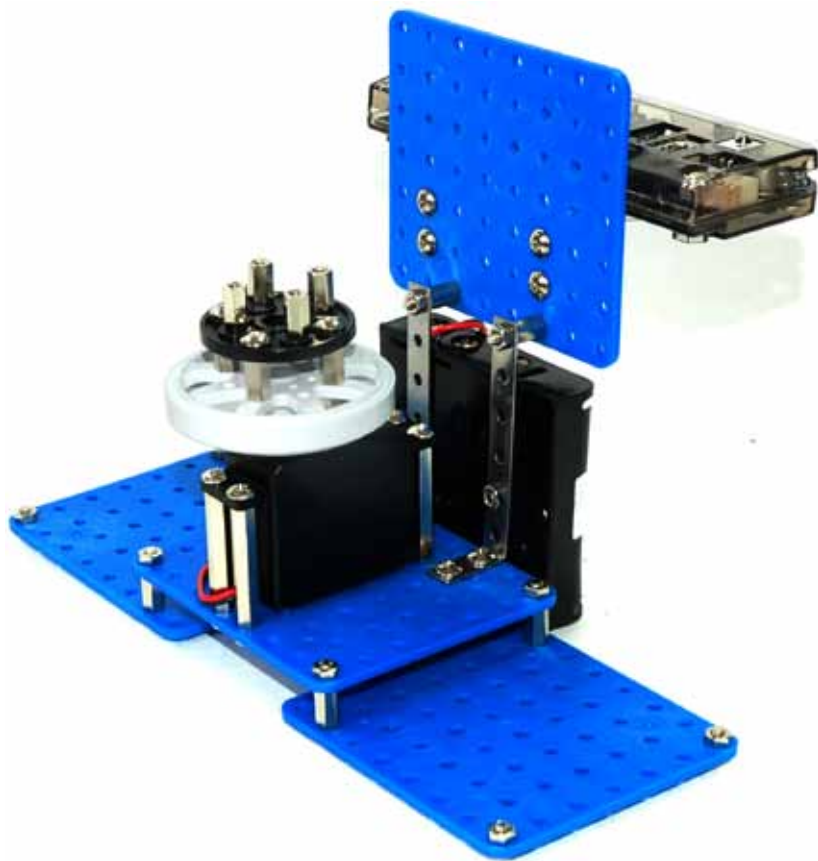
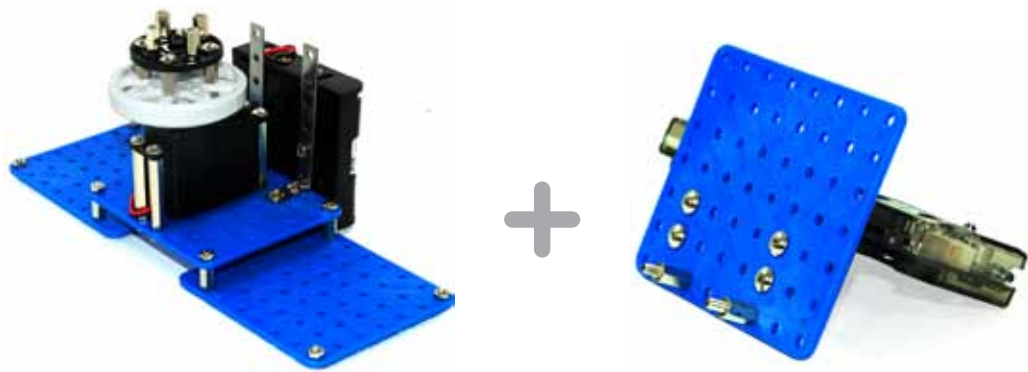


12



 X 2  X 2





14



X 12



X 12

15



X 8



X 8

16



X 1

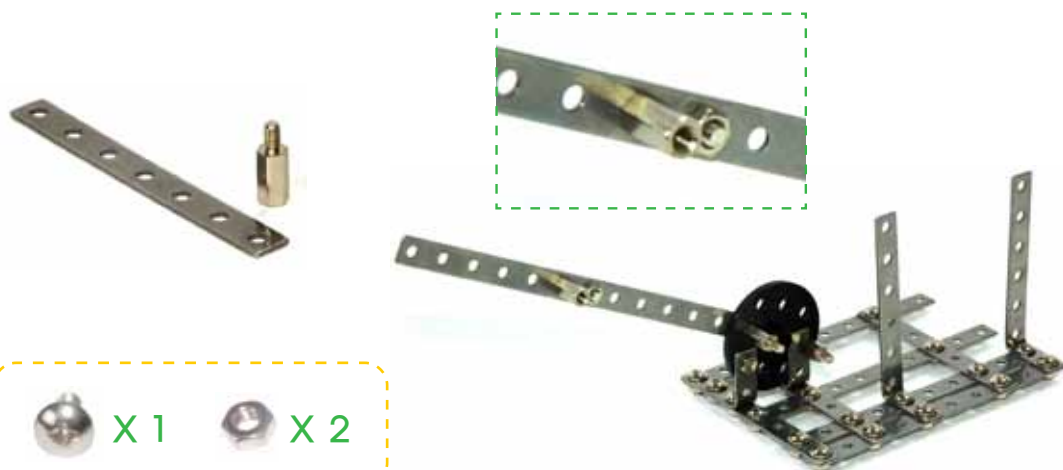


X 1

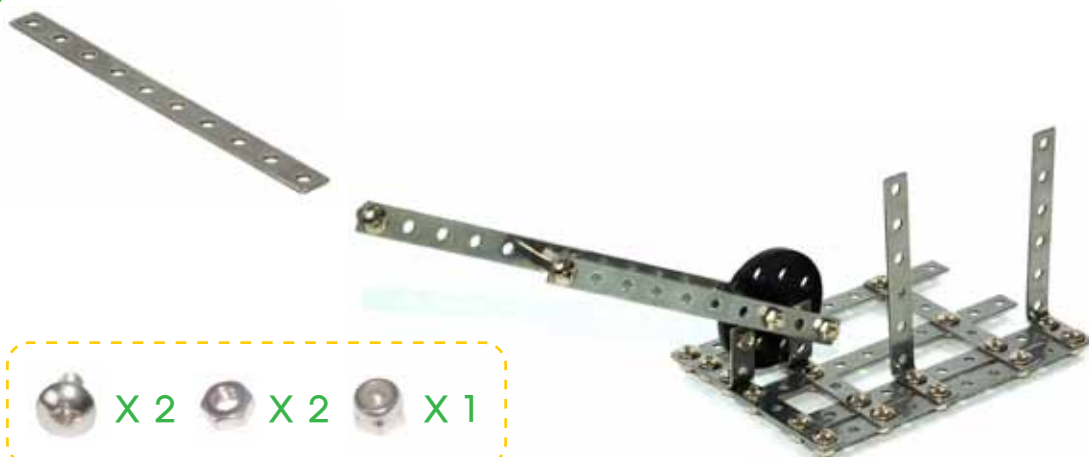
17

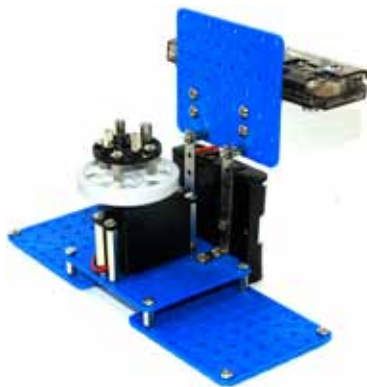


18



19

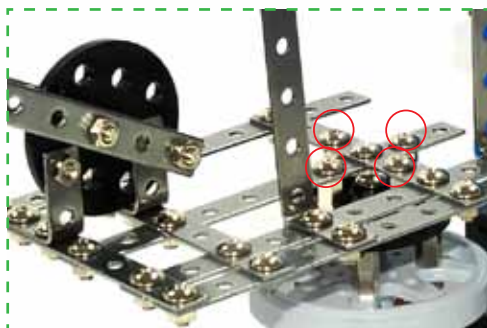
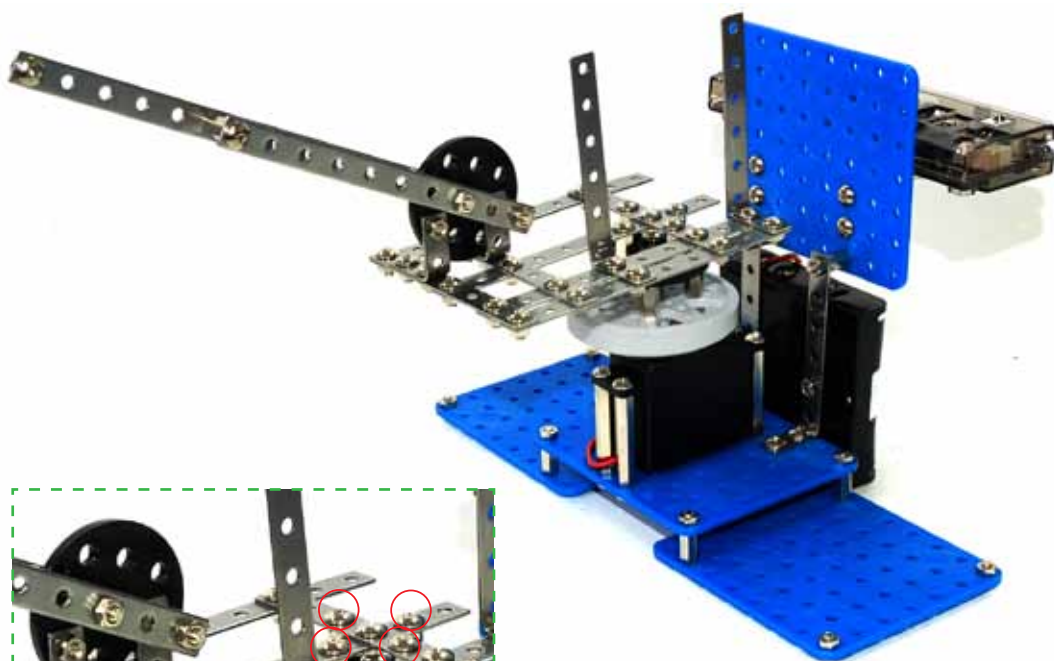


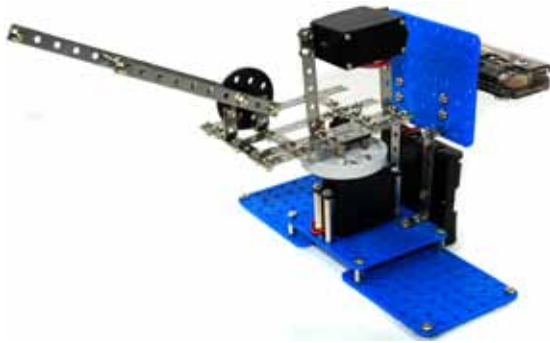


+



X 4





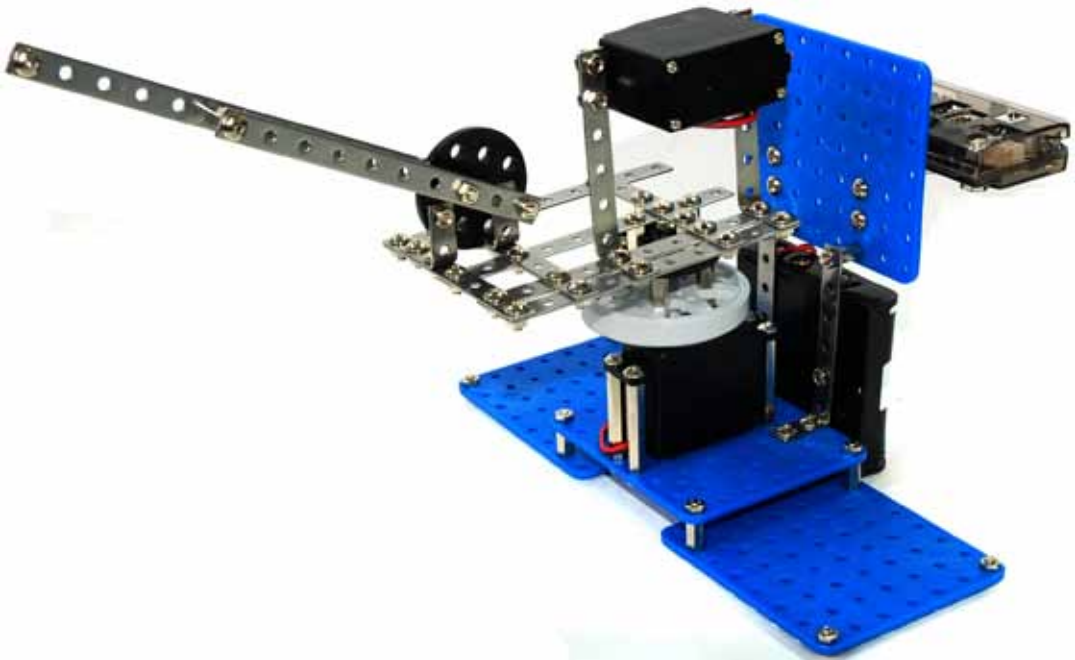
+

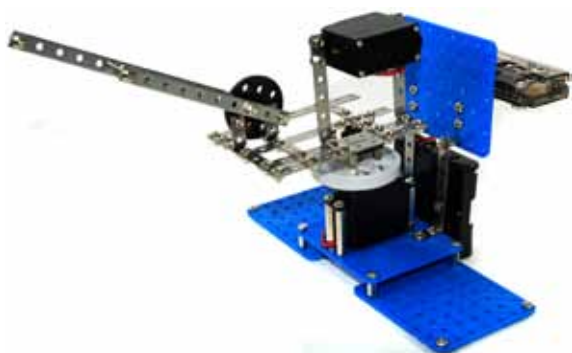


X 4

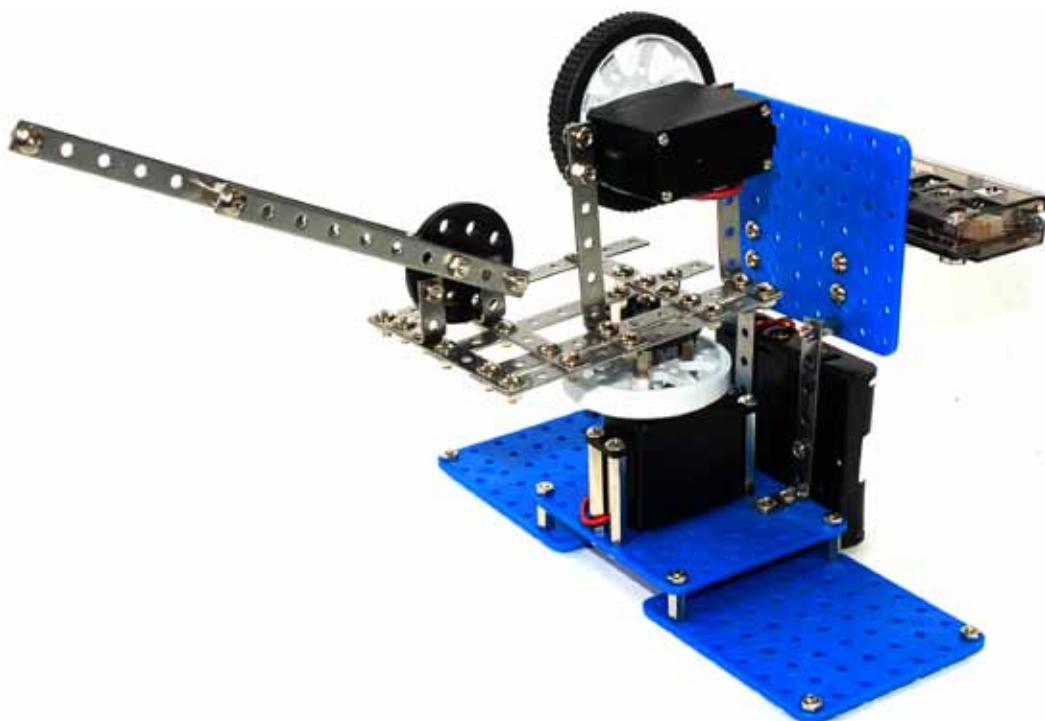


X 4

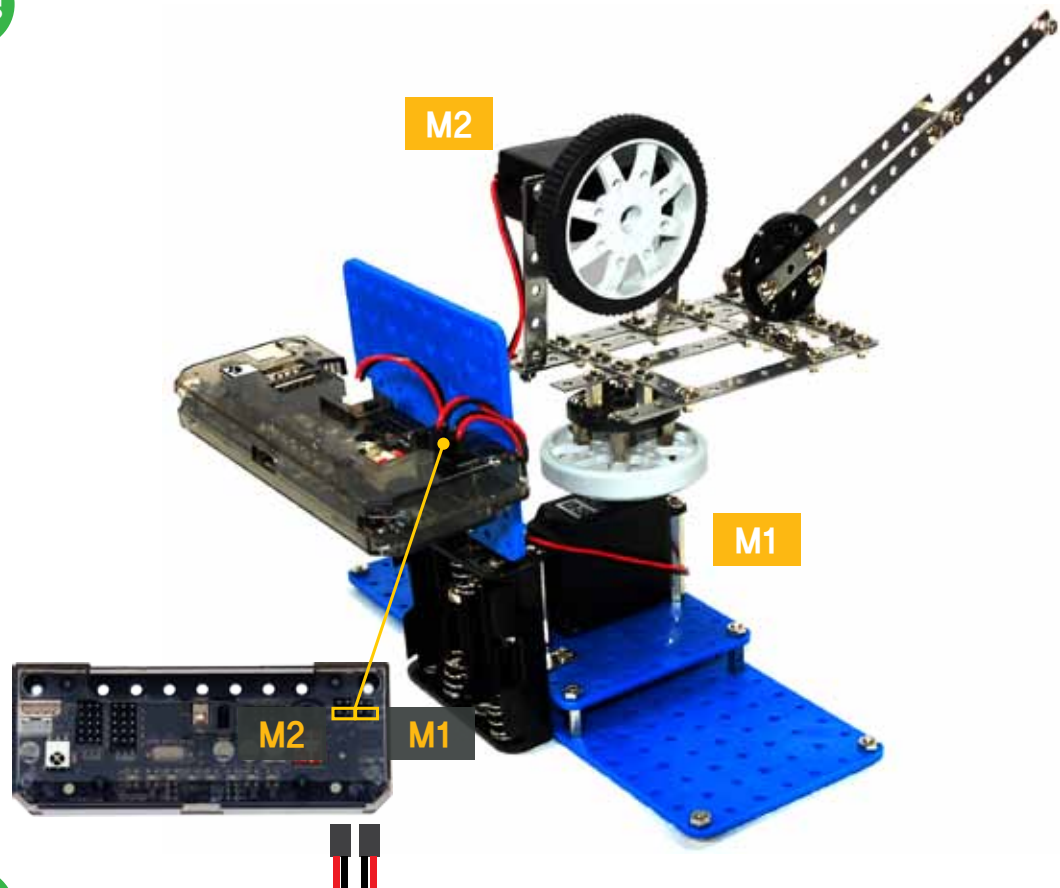




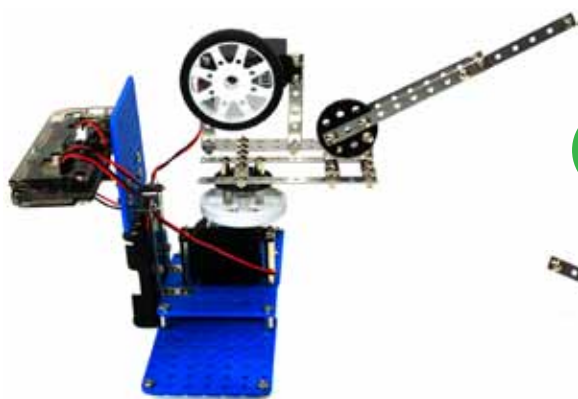
X 1



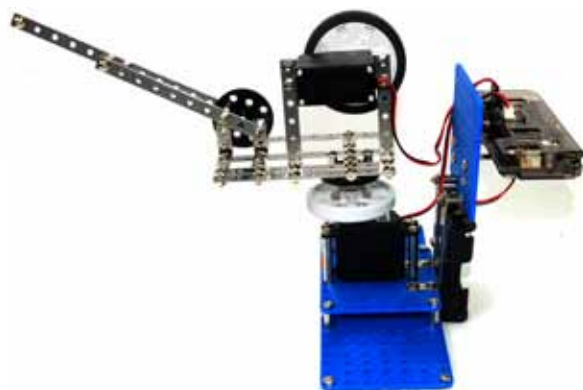
완성



좌



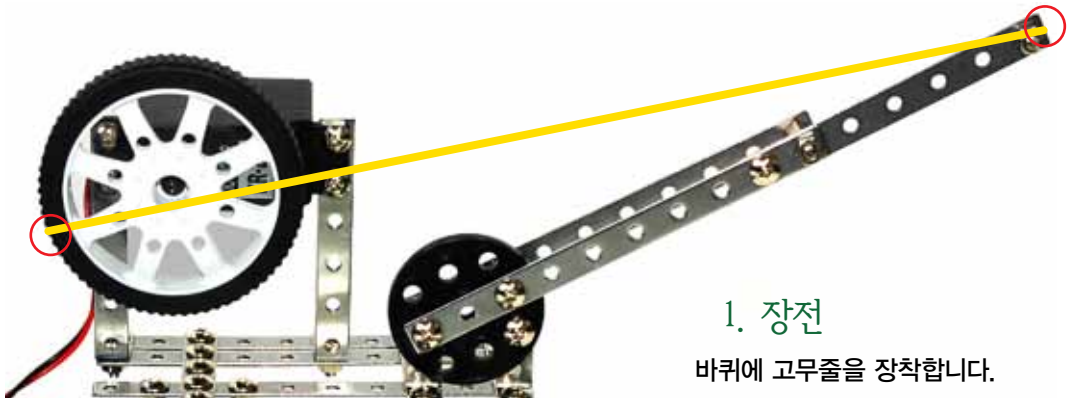
우



구동하기



터렛 로봇은 프로그램 모드 8번을 선택하여 구동합니다.



1. 장전

바퀴에 고무줄을 장착합니다.



2. 조준

왼쪽과 오른쪽 센서를 손으로 감지 시키면
발사대 이동합니다.



3. 발사

중앙 센서가 감지되면 모터가 회전하면서
고무줄을 발사합니다.