2019 Adeept Smart Robot Kit For Arduino QUADRUPED ROBOT





Warning

Please pay attention to the following issues:

- There are small components included in this kit. Make sure it's not reachable for children under 6 years old in case swallowing mistakenly. If accident occurs, please seek medical help immediately.
- Parental guidance recommended for young children.
- Do not place the products or the components near any AC socket or other circuits to avoid electric shock.
- Keep away from any liquid or flame when using the product.
- Store the product in amicable environment, avoid extreme temperature and humidity.
- Turn off the power after use.
- Do not touch the moving part of the product or interfere it with any physical objects or signals in case damages to the product or fire generated by over heat.
- Product may be warm during use.
- Do not reverse the cathode and anode of the power in case damages to the circuit.
- Refer to instructions before use.
- Handle the product gently, avoid vigorous shaking or slamming.

About

Adeept is a technical service team of open source software and hardware. Dedicated to applying the Internet and the latest industrial technology in open source area, we strive to provide the best hardware support and software service for general makers and electronic enthusiasts around the world. We aim to create infinite possibilities with sharing. No matter what field you are in, we can lead you into the electronic world and bring your ideas into reality.

The code and manual of our product are open source. You can check on our website: http://www.adeept.com/

If you have any problems, feel free to send an email for technical support and assistance: support@adeept.com

On weekdays, we usually will reply within 24 hours. Also welcome to post in our official forum: http://www.adeept.com/forum/

Copyright

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1.Component List

1.1.Acrylic Plates



The acrylic plates are fragile, so please be careful when assembling them in case of breaking. The acrylic plate is covered with a layer of protective film. You need to remove it first.Some holes in the acrylic may have residues, so you need to clean them before use.

1.2. Machinery Parts

M2 Nut	M3 Nut	M2*8 Screw	M2*14 Screw	M2.5*8 Screw
S X28	2 X21	X24	X4	X14
www.adeept.com	www.adeept.com	www.adeept.com	www.adeept.com	www.adeept.com
M3*8 Screw	M3*10 Screw	M3*15 Nylon	M3*20 Nylon	M3*22
X36	X19	Standoff X4	Standoff X4	Standoff X4
www.adeept.com	www.adeept.com	www.adeept.com	www.adeept.com	www.adeept.com
M3*40 Nylon Standoff X6 www.adeept.com	M3*8 Countersunk Head Screw X2 www.adeept.com	M2.5*4 Screw X2 www.adeept.com	M1.7*6*6 Self-tapping Screw X12 www.adeept.com	M1.4*6 Self-tapping Screw X4 www.adeept.com
M2*6 Copper Standoff X4 www.adeept.com	M2.5*11 Copper Standoff X2 www.adeept.com			

1.3.Electronic Parts







1.4.Tools



1.5.Self-prepared Parts



18650 battery specification:

It is recommended to use lithium battery above 3000mAh and without overcurrent protection. The power supply current requirement is above 3A. Using 18650 lithium battery with overcurrent protection function, 18650 battery whose capacity is less than 1700mAh, 18650 battery specially for strong-light flashlight, 18650 battery with power shortage or counterfeit lithium battery produced by informal manufacturers will cause the unstable work of the robot, power cut and even damage to the Raspberry Pi and robot. The robot can be turned on normally, but the robot will automatically restart or shut down after, also because of the problem caused by the 18650 battery.

2. Install the software

2.1.Install the Arduino IDE

1.Type the arduino.cc in the browser and download the arduino IDE.

\leftrightarrow Arduino - Home × + \leftrightarrow \rightarrow C \land \Rightarrow https://www.arduino.cc			
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	HOURLY BUILDS	BETA BUILDS	
	Download a preview of the incoming release with the most updated features and bugfives.	Download the Beta Version of the Arduino IDE with experimental features. This version should NOT be used in production.	
	Windows Mac OS X (Mac OSX Mountain Lion or later) Limux 32 bit , Limux 64 bit , Limux ARM, Limux ARM64	Windows Mac OX (Mac OSX Mountain Lion or later) Linux 32 bit, Linux 64 bit, Linux ARM, Linux ARM64	
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(remember your installation directory)

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Adeept www.adeept.com

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2.2. Install the library files

Enter https://www.adeept.com/learn/ on browser, and download the code, library

files and driver file.



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		Store Forum Blog	Learn Videos Wiki	
	nr Robot Kit			
	PiCar-A WiFi 3WD Smart Robot Car Kit for Item Code: ADR011	Adeept RaspArm Robotic Arm Kit for RPI Item Code: ADR017	Adeept DarkPaw Spider Robot Kit for RPI Item Code: ADR016	
	Adeept RaspClaws Spider Robot Kit for RPi Item Code: ADR015	Adeept AWR 4WD Smart Car Kit for RPi Item Code: ADR014	Adeept RaspTank Smart Robot Car Kit for RPi Item Code: ADR013	
	Mars Rover PiCar-B Smart Robot Car Kit for Raspber Item Code: ADR012	Adeept New Robotic Arm Kit(V3.0) for Arduino Item Code: ADA031	Omnidirectional Wheels Smart Car Kit for Arduino Item Code: ADA030	
	2-Wheel Self-Balancing Upright Car Robot Kit for A Item Code: ADA024	3WD Bluetooth Smart Robot Car Kit for Arduino Item Code: ADA021	Hexapod Spider Robot Kit for Arduino Item Code: ADA022	
	4WD Remote Control Smart Car Kit for Arduino Item Code: ADA017	Adeept Quadruped Robot Kit for Arduino Item Code: ADA032		
	🔯 Arduino			
	Indoor Environment Monitoring Kit Weather Item Code: ADA018	RFID Starter Kit for Arduino UNO R3 Item Code: ADA006	Ultimate Starter Kit for Arduino Mega2560 Item Code: ADA010	
	Ultimate Starter Kit for Arduino UNO R3 Item Code: ADA008	Super Starter Kit for Arduino UNO R3 Item Code: ADA002	Project 1602 LCD Starter Kit for Arduino Item Code: ADA005	
	Ultrasonic Distance Sensor Starter Kit for Arduino	Starter Kit for Arduino UNO R3	Primary Starter Kit for Arduino UNO R3 with 27	~

Copy the four library files Adafruit_NeoPixel, Servo,IRremote and SR04 to the libraries file in the installation directory of Arduino IDE.

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IKremote		
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3 Servo		
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Adeept driver 2,811,869 2,81	11,869 8B7B4C	
		Total 5 folders and 2,823,471 bytes in 2 files











2.3.Install the driver

1.Connect the control board and open Arduino, you will see the serial port is not accessible, meaning that you have not installed the serial port driver.

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ww.adee	E	Serial Plotter	Ctrl+Shift+L	
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sept driver		Programmer: "AVRISP mkII" Burn Bootloader	•	
Johren				
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2.Open the driver program, install corresponding driver according to the computer operating system.

Computer	→ Adeept driver → File Edit View Tools Help	▼ 49 Search Adeept driver	
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4.Now you will find the Arduino serial port is accessible (different computer configuration has different serial port).



2.4. Upload program.

1.Turn on the power and switch program upload to 0.



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t Sketch Tools Help		
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Se Serial Plotter Ctrl	Shift+L	
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char motorspeed = 20;	Arduino/Genuino Mega or Mega 2560	
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// char a,b,c,d;	Arduino Leonardo ETH	
char movespeed = 20;	Arduino/Genuino Micro	
<pre>int anglerange =4;</pre>	Arduino Esplora	
	Arduino Mini	
char angle0 = 105;	Arduino Ethernet	
char angle1 = 95;	Arduino Fio	
char angle2 = 90;	Arduino BT	
char angle3 = 103;	LilyPad Arduino USB	
char angle4 = 115;	LöyPad Arduino	
char angle5 = 90;	Arduino Pro or Pro Mini	
char angle6 = 85;	Arduino NG or older	
char angle7 = 85;	Arduino Robot Control	
char angle8 = 90;	Arduino Robot Motor	
char angle9 = 75;	Arduino Gemma	
char angle10 = 70;	Adafruit Circuit Playaround	
char angle11 = 90;	Arduino Yún Mini	
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3.Select serial port(different computer configuration has different serial port)

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20 Se 21 Se	Board: "Arduino/Genuino Uno"	,			
22	Port "COM108"	Serial ports			
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5.Upload program.

Two sets of code are provided, the infrared remote control (four_feet_robot_wifi) and wifi control (four_feet_robot_infrared). Upload the code according to your need.



Because the servo has a certain angle error, when you finish installing the servo, you may find that the four legs of the robot cannot stand on the same level, and you need to fine-tune the angle through the program. (The variable angle0-angle11 corresponds to 12 servos respectively)





6.After uploading, turn off the power and switch to 1, and then turn it on.







After the Wi-Fi and attitude sensor are debugged (about 30 second), LED changes to blue.

Now you can start to control the robot. (Note: After turning on the power, lay flat the robot when the LED does not turn to blue yet. Do not move the robot during the process because the attitude sensor is calibrating and reading the data.)

Install the servo: When the LED turns blue, install the servo (do not turn off the power).

3.Assembly

3.1.Preparations before Assembly

1.Connect the Adeept Ultrasonic Module with 4-Pin wire.



3.2. Servo debugging

3.3 Install and Remove Batteries

1.Put two 18650 batteries in 18650 Battery Holder Set according to the following method.

In the following installation process, it is required to connect the servos to the AdeeptPixie The AdeeptPixie will automatically check the servo angle and rotate it to the appropriate position.

3.4 Assemble the legs

The following is the installation of one of the legs. For the other three legs, please refer to the following installation.

The above is the installation of the leg on one side of the robot. For the installation of the other side of the leg, refer to the picture below (the legs on both sides are symmetrical).

3.5 Assemble the other parts of the robot

1.Assemble the battery holder.

Install the rocker arm.

36

Install the lights.

Assemble the legs with the acrylic plate with the rocker arm installed (the servo needs to be in the state of debugging)

Assemble Adeept Ultrasonic Module.

4. Program debugging

After the assembly is completed, the error of the servo itself will cause an angle de viation of the robot's foot. At this time, each leg of the robot needs to be adjusted to the correct angle as shown in the following figure by modifying the program. Only then the robot can work normally. Refer to the following link for video tutoria l: https://www.adeept.com/video/detail-68.html

5.Install the upper computer control software Python

5.1.Download software

1.Open the URL in your browser: <u>https://www.python.org/downloads/</u>

Download corresponding version according to your computer operating system:

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5.2. Control the robot.

1. Method of Wi-Fi control is as follows:

(1) After the LED changes to blue, connect the WIFI of ESP8266 (the name of each ESP8266WIFI module is different, but all start with ESP).

(2) Open the control software, the interface is as shown.

(3) Enter the default IP address 192.168.4.1 of the ESP8266 in the IP input box, click the connect button and you can control.

(4)You can see that there are buttons for functions of auto-stability, forward and backward, left and right turn, attack, radar scanning and automatic obstacles avoiding. Press different buttons can achieve different functions.

(5) 5Battery bar shows the battery level. Charge the battery when it shows red.

2.Method of infrared remote control is as follows:

Functions of buttons 2", "4", "6", "8", "5" and "1" respectively are forward, left turn, backward, right turn, self-stable, automatic obstacle avoidance.

(1)Note that when in self-stabilizing state, large range of motions is not recommended, and the angle of inclination is best not to exceed 30 degrees. Otherwise the processor will misjudge, resulting in incorrect data, if the processor misjudge, don't worry about it, the processor can correct itself and return to normal

(2) During the self-stabilization, if too large motion is exerted or it meets unexpected conditions, restart the robot.

(3) peration method: Press and hold W, S, A, D on the keyboard to forward, backward, turn left and turn right. Release to stop. Click Q to enter attack mode(no need to hold it). Click E to obstacles avoiding mode. Click F to self-stabilization mode. Click X to radar scanning mode. If double click WSAD with mouse, the robot will be on constant motion.

(4) Sometimes the Wi-Fi communication button may not respond, it is because that data loss may occur during Wi-Fi transmission. You can try to press other buttons, or restart the robot.

(5) The infrared remote control should be aligned with the infrared receiver. Otherwise, the data received may be incomplete, which may lead to misjudgment.

(6) When using the infrared remote control, if the LED light turns red and the color remains

unchanged for a while, that means the battery voltage is too low; And it's normal if the LED color changes from blue to red, and then changes back to blue. Because when all the motors move together, the output voltage is too large, in that case, the remaining battery power detected by the chip is too low.

6.Afterword

Thanks for purchasing our product and reading the manual! If you spot any errors or have any ideas or questions for the product and this guide, welcome to contact us! We will correct them if any as quickly as possible.

After completing all projects in the guide, you should have some knowledge of the Raspberry Pi and Robot, thus you can try to change the robot into other projects by adding more Adeept modules or changing the code for extended functions.

For more information about Arduino, Raspberry Pi, Smart car robot, or robotics, etc., please follow our website <u>www.adeept.com</u>. We will introduce more cost-effective, innovative and intriguing products!

Thanks again for choosing Adeept product and service!

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