THE BOLIDE CRAWLER
IMAGINE YOUR POSSIBILITIES

XYZrobot
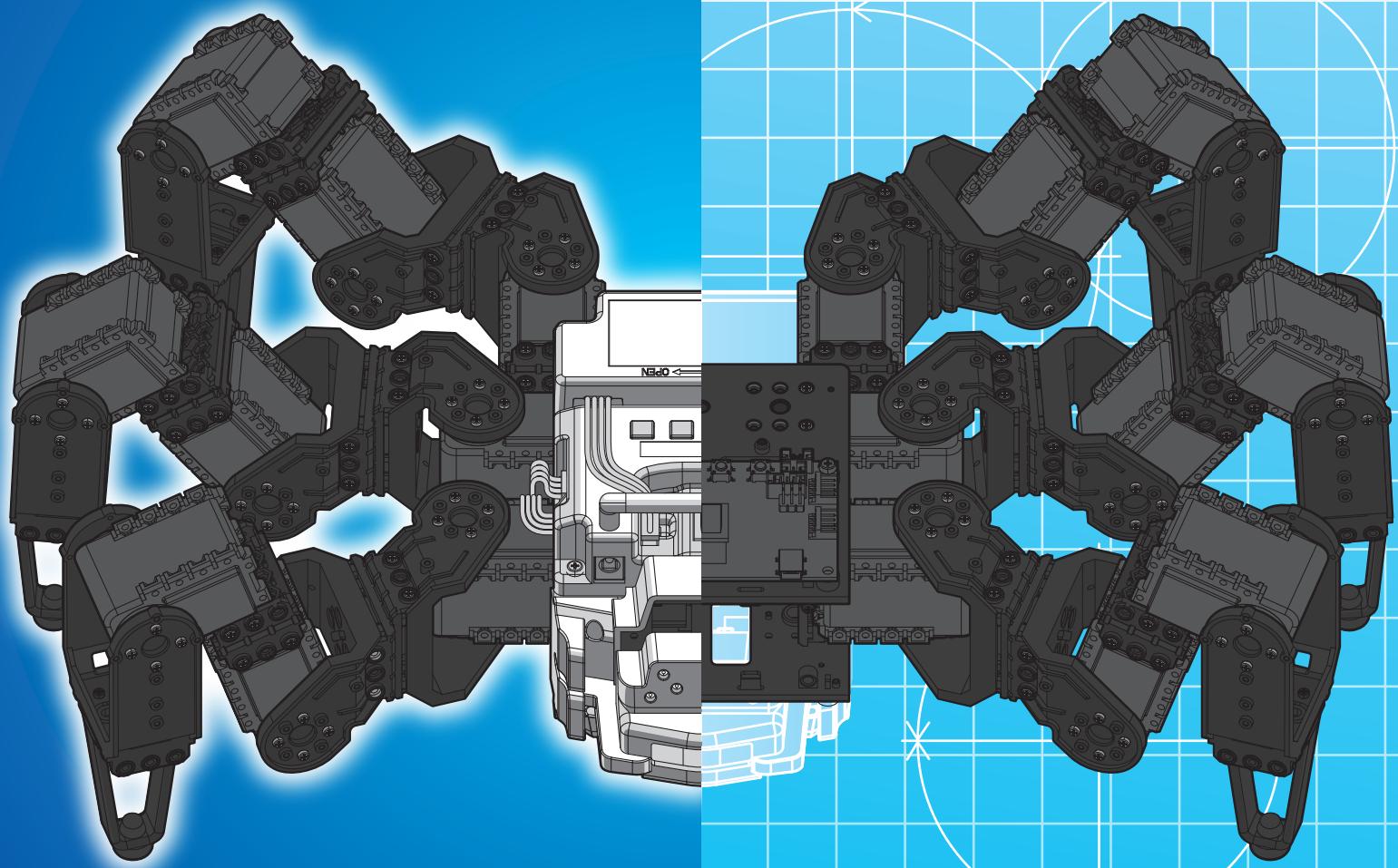
Safety Guideline
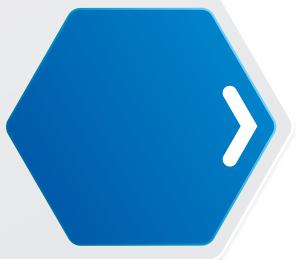
Please read the following information: failure to comply with provided information may lead to voiding the warranty.

This document covers safety, proper handling, and regulatory information for use of your Bolide Crawler.

General Precautions

Caution: To avoid injury, damage to the robot or equipment, please follow the provided guidelines.

- Please read through the directions before starting.
- The robot is not intended for use by children under 15 years old, or any person with reduced physical, sensory or mental capabilities, or lack of experience and knowledge, unless:
    - Supervised by a person responsible for the child's safety and who has read and understood these instructions.
- Keep the robot away from children under 3 years old at all times to prevent injury or damage.
- Keep components or small parts away from children.
- Keep away from pets and animals of any kind, animals may behave erratically in the presence of the robot.
- First time users should take extra care when handling the robot to minimize injury or damage.
- If the robot is operating abnormally, there is an unusual sound, smell or smoke is detected:
    - Turn the robot OFF immediately.
    - Unplug the robot.
    - Ensure the robot does not tip over or fall down.
    - Remove the battery (remove 1 screw on the back of the battery casing).
- To prevent the spread of fire, keep candles or other open flames away from the robot at all times.
- At all times, keep in mind safety first to prevent injury to individuals using or around the robot.
- Always follow installation and service instructions closely. Keep manuals for future reference.
- Review and follow all safety information provided throughout this manual.
- This guide does not cover all possible safety issues or conditions. Always use common sense and good judgment.
- Warning: Conversion or modifications to this product not expressly approved by the party responsible for compliance could void the user's authority to operate the product.
- The battery will become hot a little during charging, which is normal phenomenon.
- Please take care of this unit and its accessories, keep them clean. Please do not let this unit or accessories exposed to fire/burning cigarette, etc... Try to keep the robot and its accessories dry; please do not let this unit exposed to water or moisture.
- Please do not break, throw or trample the robot.
- Avoid installation in extremely hot, rainy or water splashing, or being placed in high temperature or moist environment.
- Please use the accessories we match for this robot.

Safety Guideline

- Never disassemble or modify the smart servo in any way, otherwise, warranty of the product will be lost. For non-human faults or breakdown, please contact authorized distributors.
- Please unplug the charging cord from the charger after charging completed to avoid over-charging.
- Keep robot away from face and body when moving.
- Do not use any tools other than those provided in the kit.

RF Exposure Warning (Bluetooth)

The equipment complies with FCC RF exposure limits set forth for an uncontrolled environment.

The equipment must not be co-located or operating in conjunction with any other antenna or transmitter.

Battery Safety Warning:

DO NOT throw the battery in fire.

DO NOT short circuit the contacts.

DO NOT disassemble the battery.

DO NOT throw the battery in municipal waste.

The symbol of the crossed out wheeled bin indicates that the battery should not be placed in municipal waste.

Important Notice for Use in Healthcare Environments:

XYZprinting Inc. products are not medical devices and are not listed under UL or IEC 60601 (or equivalent).

You can find th User Guide, the Technical Guide and these Safety Instructions ("Documentation"), visit the following:

http://www.xyzrobot.com

You can contact XYZprinting Inc. support at:

http://www.xyzrobot.com

Safety Guideline

Handling and Personal Safety

Buttons

- Before using, take a moment to locate the Power On/Off and directional buttons and familiarize yourself with the functions.

Handling

- Handle the robot with care at all times.
- Pick up the robot by the bar in the event of the following situations:
    - If the robot comes close to danger, exposure to water, or falling off a surface.
    - Before the robot knocks over objects.
    - If the robot's operation seems erratic.
- Procedure for handling in a potentially hazardous event:
    1. Pick up the robot by bar even if it is still moving.
    2. Press the Power On/Off button to turn off.
    3. Put the robot in the starting default posture.

Refer to the User Guide for powering on instructions.

- In case of a power emergency, do not touch the robot.

⚠ **CAUTION:**

Pinching Hazard

- Avoid carrying and touching the robot when it is moving, walking or getting up to avoid getting pinched.
- Keep hand and fingers out of the joint areas to avoid getting caught in between.
- To avoid injury, do not place your hands in any joint to prevent damage or personal injury.

Safety Guideline

General

IMPORTANT:

- The robot requires a clean work space to move around and perform activities.
- Do not insert any foreign objects into any of the component or internal cavities.
- Generally, do not allow or cause the robot to fall down.
- Do not exert strong force against the joints or actuators (smart servos).
- Do not grab and pull by the head or arms/legs to prevent exerting force on the joints.

Powering

Please read the user manual that came with the Bolide Crawler. It contains important installation and safety instructions.

⚠️ **CAUTION:**

The AC adapter may become hot.

- Do not use the robot when the cables are plugged in to avoid damage.
- Do not use the AC adapter to charge the battery if room temperature is above 45°C (113°F).
- For the maximum battery lifespan, fully charge the battery at least once every 3 months.
- Protect the AC adapter terminals from dirt or other foreign objects.

⚠️ **CAUTION:**

To avoid electric shock:

- Do not plug the power cables into an electrical outlet if the power cable is damaged.
- During a storm, unplug the AC adapter from the socket to protect it from damage.
- Never use an AC adapter that shows signs of damage or excessive wear.

⚠️ **CAUTION:**

Risk of fire or electric shock:

- Use only the provided AC power cable with the AC adapter. Use of any other power cable may damage the robot or AC adapter or affect your safety.
- There is no switch on the AC adapter; to disconnect it, pull the plug. Keep the plug easily accessible at all times to allow easy disconnection.
- Unplug the power adapter if:
    - The adapter is exposed to rain, liquid, or excessive moisture.
    - The adapter case has become damaged.
    - You suspect the adapter needs service or repair.
    - You want to clean the adapter.
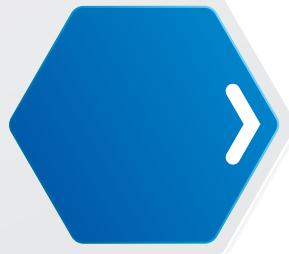
Extension Cables

⚠ **CAUTION:**

To avoid electric shock:

- Do not use multiple socket adapters or power extension cables that bypass the ground wire or disable grounding.
- When using a power extension cable or a multiple socket adapter, make sure it is grounded and has sufficient current rating. No more than one extension device at a time is recommended for use.
- If using a multiple socket adapter, take care when plugging the power cable, as some types allow incorrect plugging which could result in permanent damage to the robot, as well as cause possible electric shock and/or fire damage.
- Do not plug the robot power cables into an electrical outlet if the power cable is damaged.
- Do not connect or disconnect the power adapter with wet hands.
- Plug the robot power cables only into properly grounded electrical outlets.
- Do not use adapter plugs that bypass the grounding feature, or remove the grounding feature from the plug or adapter.
- If using an extension cable, make sure that the total ampere rating of the products plugged in to the extension power cable does not exceed the ampere rating of the extension cable.
- Use an extension cable or power board designed for grounded plugs and plugged into a grounded wall outlet.

Working Area

- Start from the default posture before turning on the robot.
- When turned off, it is best to keep the robot in the default posture without the cable plugged unless charging.
- Before starting, make sure there is enough free space for operation. This requires a radius of at least 60 cm (24 inches) around the robot to avoid obstacles.
- Generally, leave at least 60 cm (24 inches) all around the robot to avoid damage. In particular, ensure that all cabling is removed from the usable area.
- The working surface must be dry and level; thick carpets or rugs are not recommended for operational stability.
- The robot is designed for indoor use only.
- Keep the robot away from radiators, heat sources and direct sunlight.
- Operating temperatures: between 0°C and 40°C (32°F to 104°F).
- Operating humidity range: between 20% and 80%.
- Do not leave the robot unattended on the floor.

Safety Guideline

Special Procedures

General

- Never oil the joints with any kind of lubricant.
- Do not modify or open any of the actuators.
- Do not drop, crush, bend, deform, puncture, shred, microwave, incinerate any of the components. Doing so can cause fire, electric shock, damage or personal injury.
- When handling sensitive components (e.g., printed circuit board), only hold the board by the edges to prevent damage due to electrostatic discharge (ESD).
- Do not forcibly twist the robot when the power is to prevent damaging the smart servos (acuators).
- Place the robot on a flat surface prior to the use of the remote control.

Liquid Spills

⚠️ **CAUTION:**

Use extreme caution when removing wet power cables from a power socket (or extension cable) and only attempt this if it is safe to do so:

- Liquids spilt onto the robot or AC adapter may cause a short-circuit and stop the robot from working. The warranty is automatically void if any liquid seeps inside the AC adapter, whether apparent from the outside or not.
- Do not use the robot in a wet environment.
- Do not connect or disconnect the battery or AC adapter when your hands are wet.
- Do not use the AC adapter if exposed to rain, liquid, or excessive moisture.
- Do not attempt to dry the components with an external heat source such as a hairdryer or an oven.

Procedures

- If liquid has not seeped inside the torso or battery casing:
    1. Turn off the robot.
    2. Disconnect all cables, including the AC adapter.
    3. Place the robot in the default posture.
    4. Wipe the robot completely dry.
    5. When thoroughly dry, turn on the robot to continue operation.

Safety Guideline

- If liquid has seeped inside the torso or battery casing:
    1. Disconnect all cabling from the power socket then disconnect the other cabling end from the robot.
    2. Turn off the robot.
    3. Place the robot in the default posture.
    4. Dry the robot as much as possible.
    5. Disconnect and remove the battery casing.
    6. Let the robot air dry completely before installing the battery casing.
    7. Once completely dry, install the battery casing.
    8. Turn on the robot.

NOTE: For information on your warranty coverage see the Warranty in this assembly manual.

Table of Contents

Table of Contents

Prerequisites

Windows Operating System Requirements

- Windows 7 or later. Including both 32-bit and 64-bit versions
- Microsoft .Net Framework 4.5

Mac Operating System Requirements

- Mac OS X 10.8 or later

Arduino

- Arduino IDE 1.0.6

Getting Started

Introduction

The Firmware includes a XYZrobot Editor to help you define and edit action sequences. The XYZrobot Editor is easily installed on your computer, and designed to interface with current Bolide and future models.

XYZrobot Editor

The XYZrobot Editor is the software included with your Bolide Crawler robot package. The software is compatible with both Windows and Mac OS operating systems. The XYZrobot Editor allows you to create a wide variety of standard and unique poses for your Bolide Crawler, which are easily edited and stored. The software will also allow you to create action sequences, by combining the pose list in any number of combinations.

For more information about the XYZrobot Editor, visit XYZprinting Inc. at:

http://www.xyzrobot.com

Firmware

The software pack includes the following items:

- Arduino
- Arduino Library and Hardware for Bolide Y-01
- Bolide Crawler Default

Setup Your Bolide

Requirements

The following list outlines prerequisites for the installation process.

1. Assembly the Bolide Crawler; see the Bolide Crawler Assembly Guide.
2. Download the **Firmware** from www.xyzrobot.com.

Overview of Installation Process

Review all instructions and information prior to starting the actual installation, to avoid hardware damage, difficulty during installation, or personal injury.

The document is organized to give the reader a straightforward account of the installation process. The sections are ordered sequentially as follows:

- Installing the XYZrobot Editor Software
- Installing Arduino Application
- Installing the Bolide Crawler Editor Driver

Installing the XYZrobot Editor Software

Overview

The XYZrobot Editor is designed specifically to allow for easy creation of poses and action sequences for use with the Bolide Crawler.

Prior to installation, you will need to have the Adruino software and the Bolide driver code installed on your computer system and MCU board, respectively.

See the following section for step-by-step instructions on installing the XYZrobot Editor software.

Installing the XYZrobot Editor

Before installing the Editor, download the driver from http:\\www.xyzrobot.com.

1. Locate the downloaded driver file.

2. Click **setup.exe** to run the application.

   The Launching Application window displays. Follow the on-screen prompts to continue.

   NOTE: At the time of writing, the file and folder names were under development. File and folder names may differ after production.
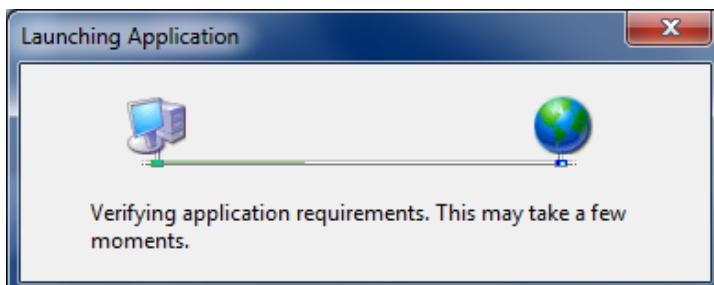
3. Click **Install** to install the XYZrobot Editor.

A status screen displays the installation status. Once the installation is complete, the XYZrobot Editor software opens.

NOTE: The default screen may not reflect your actual device.
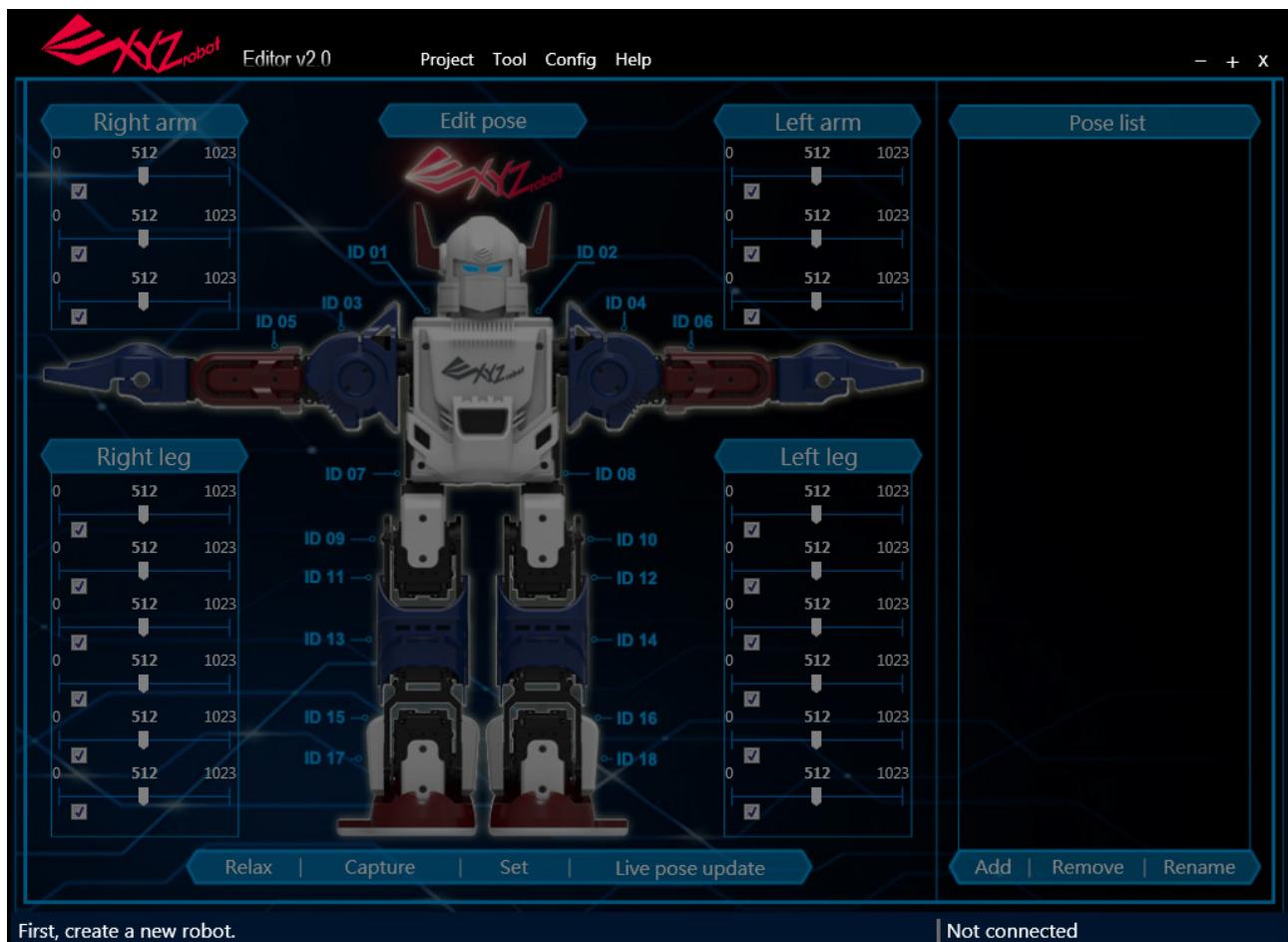
NOTE: A security prompt may display requiring authorization to open the software. To continue with the procedure, click **OK** to continue or cancel to end the process.

Uninstalling the XYZrobot Editor

To uninstall the XYZrobot Editor software, follow these step-by-step instructions.

1. Close the XYZrobot Editor.
2. On Windows, click **Start > Control Panel** to open the computer's settings menu.
3. Click **Uninstall** a program to open the Uninstall or change a program menu.
4. Select XYZrobot Editor v1.0 from the list and click **Uninstall/Change**.

For Mac users:

1. Drag the app from the Applications folder to the Trash (located at the end of the Dock).
2. Choose **Finder > Empty Trash**.

The XYZrobot Editor application is removed from the program list.

WARNING: Emptying the Trash bin permanently removes the content, which is no longer available.

NOTE: The screens and procedure may vary slightly depending on the operating system in use.

Updating the Software

During the course of normal operations, the XYZrobot Editor automatically checks for updates and installs them. When new updates are available, you are notified before the process starts.

Arduino Application

Before you begin using the XYZrobot Editor, install and configure the Arduino application. The application is required to install the Bolide Crawler drivers on your computer.

NOTE: Prior to connecting the Bolide Crawler to your computer, it may be necessary to update the USB drivers on your system. See *"Installing a USB FTDI Driver"* on page 39.

Arduino 1.0.6 Version

The Firmware supports Arduinio 1.0.6.

The Firmware allows you to continue using the current 1.06 version without the need for reinstallation.

Installing an Arduino Package

The Installer Version allows you to fully install the Arduino application in your computer system. For this version, you will need admin priviledges to being the installation process. If you do not have admin privileges, see your network administrator or use the Non-+Admin Installation version.

1. Download the Arduino software; note only version 1.0.6 is supported.

    • Windows: http://arduino.cc/download.php?f=/arduino-1.0.6-windows.exe
    • Mac OS X: http://arduino.cc/download.php?f=/arduino-1.0.6-macosx.zip

2. Click the installer file to start the installation process.

3. The Installation Options prompt displays; click on the components to de-select from the installation process. By default all components are pre-selected.

Installing Arduino for Non-administrators

The Non-Admin version is a standalone package capable of running on your system without the need to initiate the installation process. This version is not installed onto the operating system and is not registered within the system registry. It can only be accessed by opening the executable file, provided in the software package.

1. Download the Arduino software (ZIP format), only version 1.0.6 is supported.

    • Windows: http://arduino.cc/download.php?f=/arduino-1.0.6-windows.zip

2. Once downloaded, extract the ZIP package to a desired folder on your system.

The Arduino package (ver. 1.0.6) is now set up on your system.

Installing the Bolide Crawler Editor Driver

The Bolide Crawler comes with a pre-installed firmware driver. To allow you to make full use of all its features, the Bolide Crawler comes with XYZrobot Editor, which allows you to create single and sequenced movement steps. The XYZrobot Editor makes use of the Arduino open-source platform, requiring the installation of Arduino on your system (if not done so at this point), and synchronizing it to your Bolide Crawler.

The following instructions guide you through the complete installation of the driver required for the XYZrobot Editor.

1. Connect the Bolide Crawler to your computer. Connect one end of a USB cable to the computer (USB Type A), and the other end to the Bolide Crawler (USB Type Mini-B).

2. Power up the Bolide Crawler; see "Testing the Bolide Crawler" in the Assembly Manual.

3. Locate the Firmware and navigate to the following folder:

    Bolide_Y-01_Arduino_Support_File_20151201\XYZrobot_Editor_Driver (For the latest software visit http://www.xyzrobot.com).

4. Double click **XYZrobot_Editor_Driver.ino** to run the application.
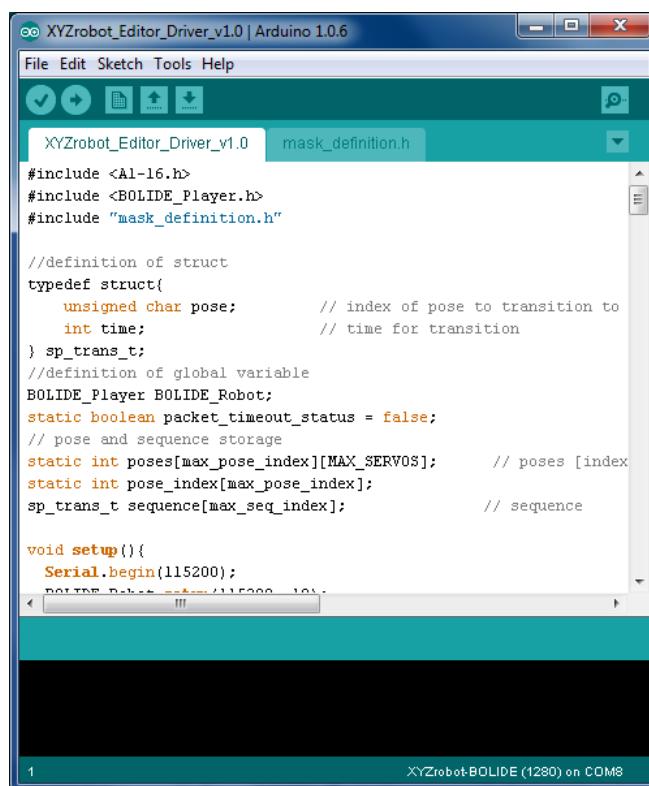
5. From the menu toolbar, click **Tools > Board** and select the option **XYZrobot-BOLIDE**.

6. Next, select the COM port associated with the Bolide Crawler. From the menu toolbar, click **Tools > Serial Port** and select the associated option.

> **NOTE:** If the device is not detected, the USB driver may not be recognized. The option to select the associated COM port will not be available. You will need to update or re-install the serial port drivers; see *"USB Drivers"* on page 39.

7. Click ✔ (Verify) to compile the codes.

After compiling, the message **Done compiling** displays on the bottom of the frame.

If there are no errors and the compiling is complete, upload the code to the MCU board.

8. Click → (Upload) to upload the codes.

After uploading, the message **Done uploading** displays and no error is identified at the bottom of the frame.

Introduction

The following section provides a detailed description of the XYZrobot Editor's interface, including step-by-step instructions on the creation of poses and action sequences for use with the Bolide Crawler robot.

Interface Menus

Main Menu

The main interface as described in the following figure is the initial display viewed when the XYZrobot Editor is opened. The following table provides a description of the menu names and a brief description of their function.

NOTE: The default screen may not reflect your actual device.
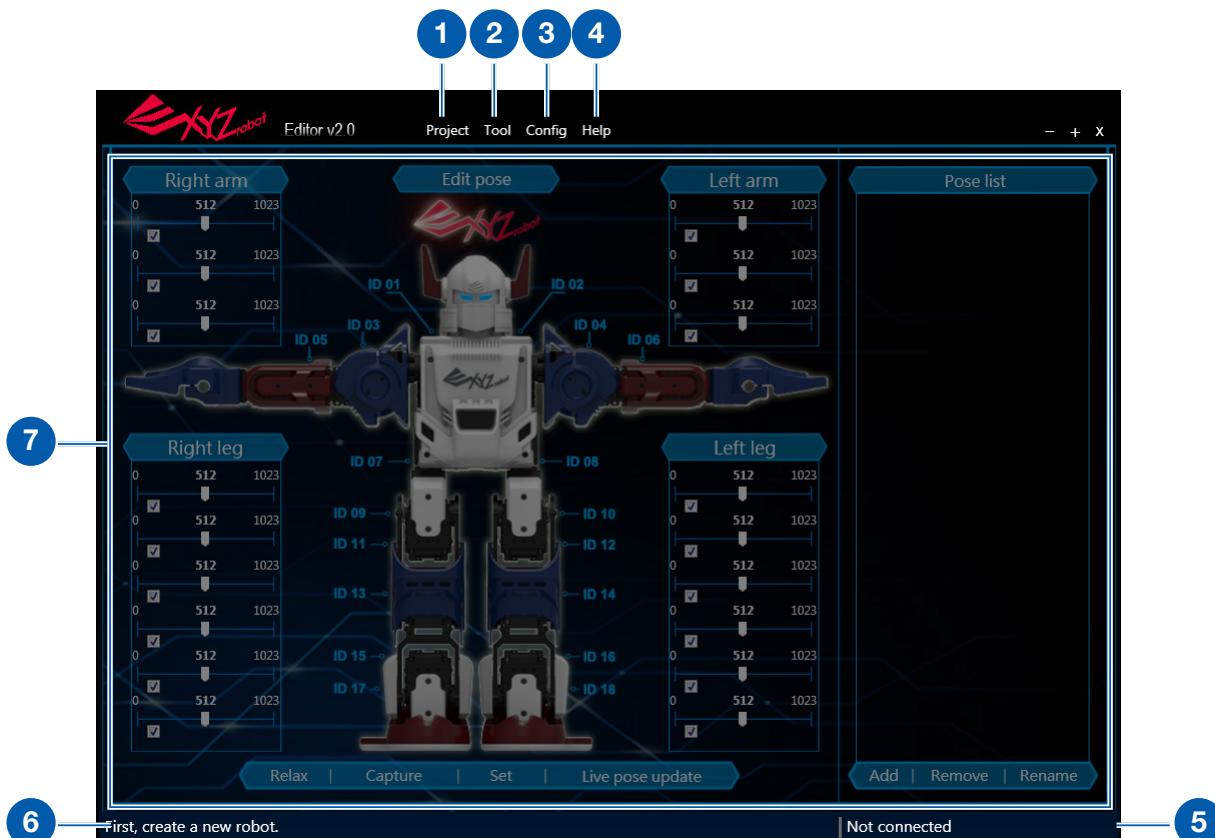
No	Item	Description
1	Project	Open to create new, open existing, save/save as projects. See *"Project"* on page 20.
2	Tool	Open to select the type of function screen to display: Pose editor, Sequence editor, Sample player, Control editor or Export to AVR. See *"Tool"* on page 20.
3	Config	Open to select the Port Settings option. See *"Config"* on page 20.
4	Help	Open to select the About, Serial number and Language settings options. See *"Help"* on page 20.

No	Item	Description
5	Connection Status	If a Bolide Crawler device is detected, the dialogue displays a device connected status.
6	Description bar	The dialogue displays text description of the last initiated action.
7	Configuration Area	The configuration area displays the actual position of each smart servo, as well as editing functions to allow you to create unique movement and sequence definitions. See *"Main Menu"* on page 19.

Project

Item	Description
New	Create a new project.
Open	Open a saved project file. If a project is currently open, you will need to close it before opening the new project.
Save	Save the current project.
Save As	Save the current project under a different name.
Import	Import previously saved settings into the open project.

Tool

Item	Description
Pose editor	Switch main menu to pose editor.
Sequence editor	Switch main menu to sequence editor.
Sample player	Switch main menu to sample player.
Control editor	Switch main menu to control editor.
Export to AVR	Export the current settings to a .h file.

Config

Item	Description
Port setting	Select the current communication port.

Help

Item	Description
About	Show the information about the XYZrobot Editor.
Serial number	Show the serial number of the connected device.
Language	Select an interface language: English, Traditional Chinese or Simplified Chinese.

Operations

03

Pose Editor

No	Item	Description
1	Pose list	Displays the list of all created pose descriptions.
2	Rename	Rename the selected pose.
3	Remove	Remove the selected pose.
4	Add	Create a new pose item.
5	Live Pose Update	Initiate to adjust the smart servo positions directly. Each setting adjustment directly moves the smart servo position. **WARNING:** The Live Pose Update allows you to directly adjust the smart servo position. Do not place your hands around the Bolide Crawler. Ensure there is sufficient space around the Bolide Crawler for unobstructed movement, to avoid personal injury or damage to the unit.
6	Set	Send the current desired position settings to the Bolide Crawler board. The signal is then sent to each smart servo to match the desired position.
7	Capture	Capture the pose on the Bolide Crawler to the corresponding smart servos, for the selected pose.
8	Relax	Stops the electric pulse signal to the smart servo, allows for manual rotation of the rotor.

No	Item	Description
9	Smart servo ID	Click to move the slide bar and change the smart servo's actual position.
		By default, the neutral position is set at 512. A reading of 0 sets the desired position to 0° degrees, while a reading of 1023 defines a 330° turn.
		NOTE: The function is only accessible when a project is connected and a pose is selected.
10	Slide bar	Move the slide bar to manually adjust the actual position of the smart servo.
		NOTE: A reading of 0 sets the desired position to 0° degrees, while a reading of 1023 defines a 330° turn. The smart servo cannot rotate outside of these parameters.

Sequence Editor
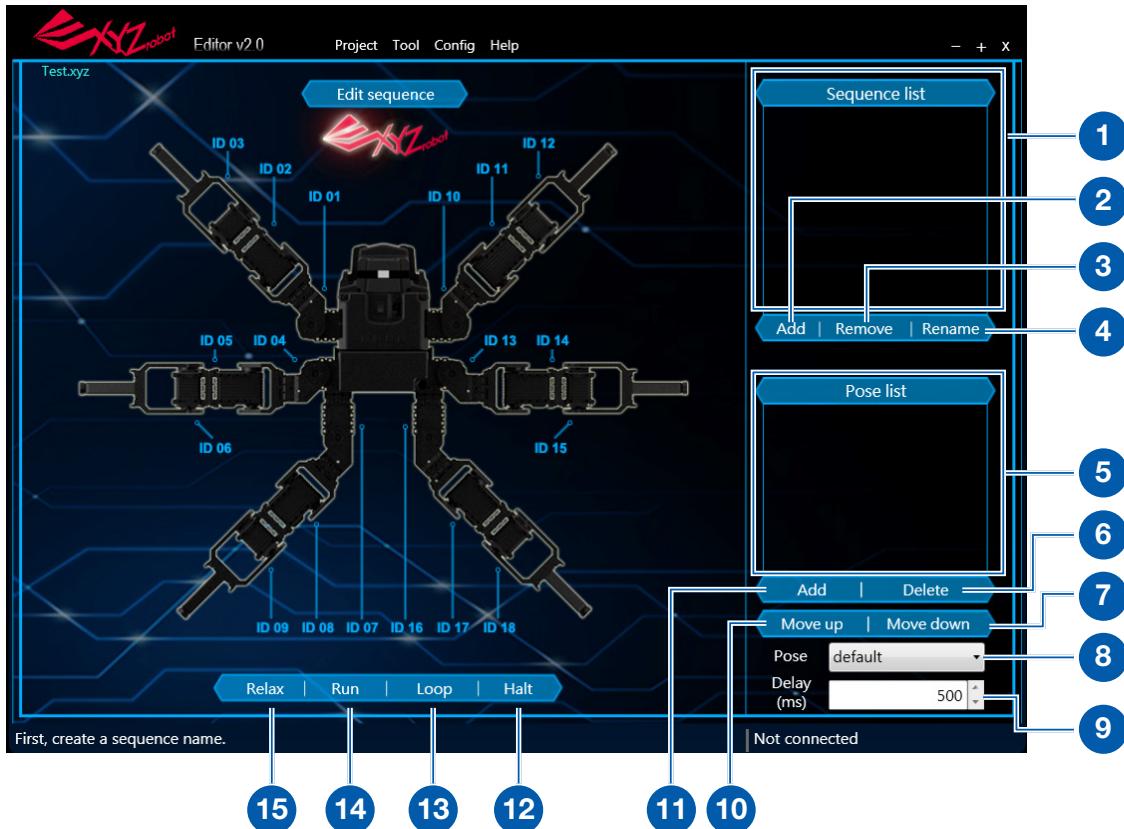
No	Item	Description
1	Sequence list	List the sequences.
2	Add	Create a new sequence list.
3	Remove	Remove the selected sequence.
4	Rename	Rename the selected sequence.
5	Pose list	List the pose entries for the selected sequence.
6	Delete	Delete the selected pose from the sequence.
7	Move down	Move the order of the selected pose down in the order.
8	Pose	Click the drop-down menu to select a pose.
9	Delay (ms)	Click the selector arrows to adjust the variable, or type a specific number and press **Enter** to manually set a delay variable.
10	Move up	Move the selected pose up in the order.
11	Add	Add a pose action to the sequence entry.
12	Halt	Initiate a stop command when a sequence is running.
13	Loop	Initiate a continuous run command for the selected sequence.
14	Run	Initiate a run command for the selected sequence.
15	Relax	Stops the electric pulse signal to the smart servo; allows for manual rotation of the rotor.

Sample Player
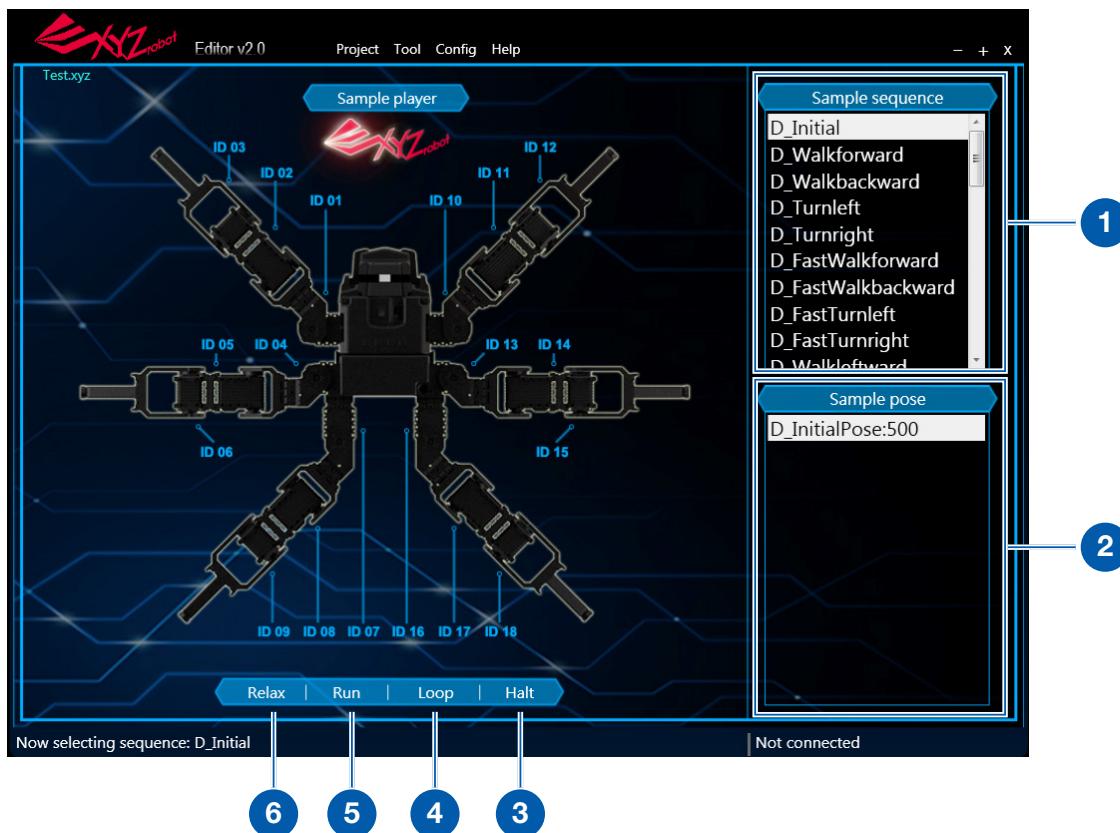
No	Item	Description
1	Sample sequence	Select a sequence entry to initiate the action sequences on the robot.
2	Sample pose	Select a pose entry to initiate the action on the robot.
3	Halt	Initiate a stop command when a sequence is running.
4	Loop	Initiate a continuous run command for the selected sequence.
5	Run	Initiate a run command for the selected sequence.
6	Relax	Stops the electric pulse signal to the smart servo, allows for manual rotation of the rotor.

Control Editor
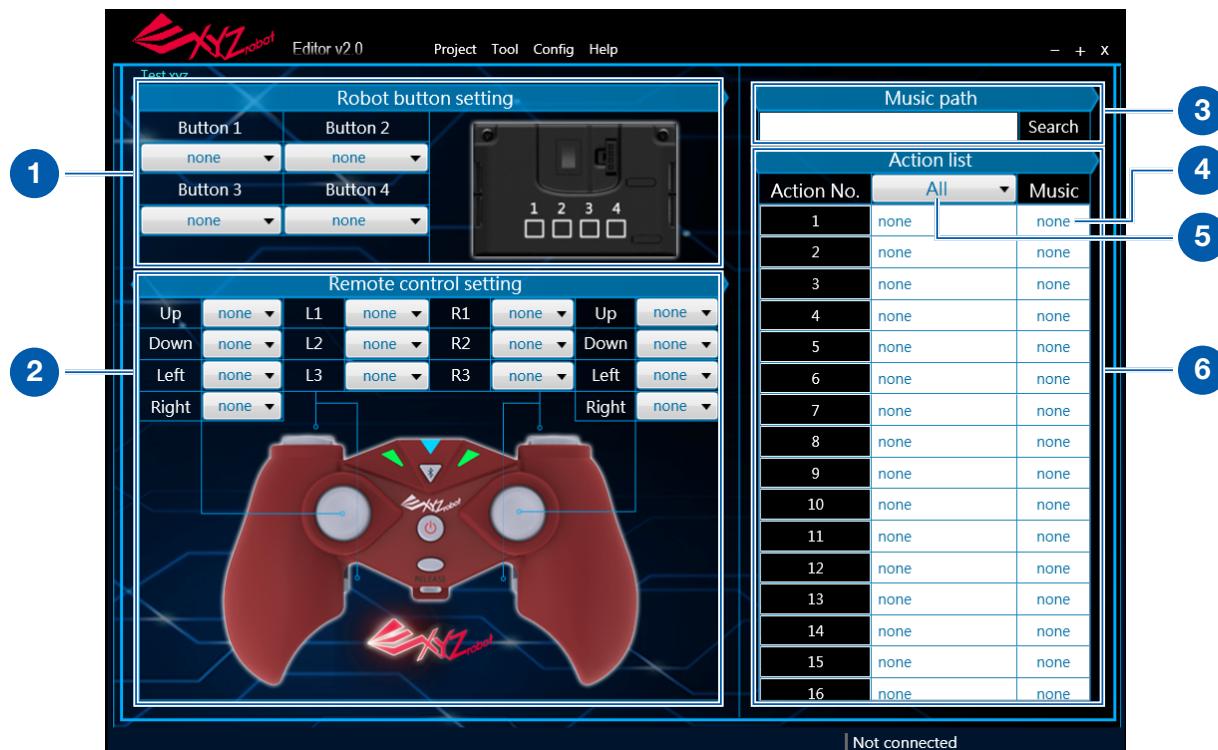
No	Item	Description
1	Control Panel Settings	Click a drop-down menu to select the action entry to associate with the control panel button.
2	Remote Control Settings	Click a drop-down menu to select the action entry to associate with the remote control button.
3	Music path	Click **Search** to select the folder path for the audio source.
4	Music File	Click to select an audio file (WAV formats only) from the defined music path folder.
5	Action list type	Click the drop-down menu to select the type of entries to display: All, Default, Custom.
6	Action list	Click the adjacent field to select an action entry to associate with the selected action number.

Basic Editing

The XYZrobot Editor provides a simple and effective method to create, edit and remove pose and sequence entries.

The following section provides step-by-step instructions for creating complete pose and sequence entries.

Creating a Pose

Before you open the XYZrobot Editor, it is necessary to connect the Bolide Crawler and computer through a USB cable.

The following procedure provides detailed instructions to allow you to create a pose:

1. Connect the Bolide Crawler to your computer. Connect one end of a USB cable to the computer (USB Type A), and the other end to the Bolide Crawler (USB Type Mini-B).

2. Once connected, power up the Bolide Crawler, see "Testing the Bolide Crawler" in the Assembly Manual.

3. Locate and open the XYZrobot Editor application.

4. From the toolbar, select **Projector > New**.

5. Enter a new project name in the name field.

6. Click the **Model** drop-down field and select **Bolide Crawler**.

7. Click **OK** to continue or **Cancel** to return to the previous menu.

8. From the toolbar, select **Config > Port Setting** to open the option window.

9. A list of available ports displays in the window. Select the port that is assigned to the connected Bolide Crawler.

10. Click **Ok** to continue.
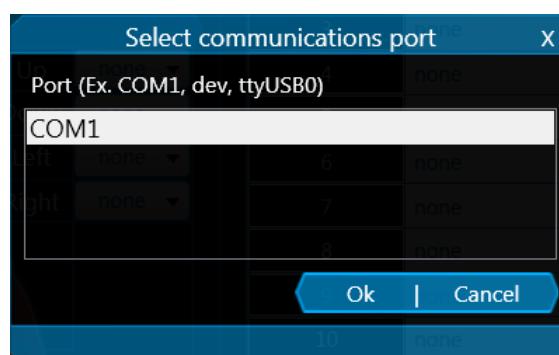
11. Select **Tool > Pose Editor**.

12. Under Pose List, click **Add** to create a new pose.

13. The New pose settings window displays. In the Pose name field, enter a name for the pose and click **Ok** to create the new entry.
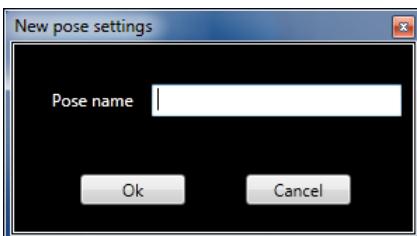
The New Pose is configured with the default settings. This function allows you to create pose entries which can be modified and saved, and used to create sequence entries.

14. Now that the pose is created, it appears in the Pose List column. Locate your desired pose entry and select it to edit the settings.

You can edit a pose by one of two ways, physically move the smart servo position or through the use of the slide bar function in the Pose Editor. The following instructions provide a step-by-step instructions of both procedures.

WARNING: Keep hand and fingers out of the joint areas to avoid getting caught. To avoid injury, do not place your hands in any joint.

   a. In the bottom toolbar, click **Relax** to release the smart servos and allow you to move them freely.

     NOTE: To avoid damage the Bolide Crawler, please lay it down or grip it firmly by the bar on the back of the Bolide Crawler (over the power switch), before clicking the **Relax**.

   b. Select a smart servo and adjust it to a desired position. This is the position that will be associated with the selected pose.

   c. Click **Capture** to save the settings to the selected Pose.

   d. Click **Set** after adjusting slide bars.

   OR

   a. Select a pose from the Pose List.

   b. Click **Live Pose Update** to adjust the actual position of a selected smart servo.

   c. Select a smart servo, and adjust the slide bar to a desired smart servo position.

   d. Click **Set** after adjusting slide bars.

Creating a Sequence

Follow the procedure to create a sequence:

1. Connect the Bolide Crawler to your computer. Connect one end of a USB cable to the computer (USB Type A), and the other end to the Bolide Crawler (USB Type Mini-B).

2. Power up the Bolide Crawler; see "Testing the Bolide Crawler" in the Assembly Manual.

3. Locate and open the XYZrobot Editor application.

4. From the toolbar select **Tool > Sequence List**.

5. Click **Add** to create a new sequence entry. The **New sequence settings** window displays.

6. In the open field, enter the name of the sequence entry and click **Ok** to continue.
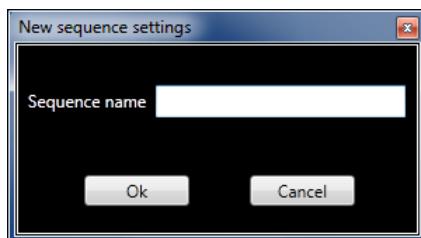
7. Under the Pose List column, click **Add** to add an available pose to the selected sequence list.

    The newly added pose entry is added to the bottom of the existing sequence list with the default Delay timer (500 milliseconds).

8. To modify the delay timer for a pose, click the **Pose** drop-down menu and click on the up and down arrows on the **Delay** frame to adjust the time (milliseconds). Alternatively, you can enter a variable by typing it in the Delay field.

9. Once you've edited the pose you will need to add it back in to the list. Click **Add** to add the pose into the selected sequence.

    You can also organize the pose order of appearance to customize the order in which the pose list is executed.

10. To re-order a pose, under Pose List, select a pose entry and click **Move Up** or **Move Down** to position the entry into your desired order.

11. Once the sequence is designed, you can initiate a test to view the pose selections performed by the Bolide Crawler.

12. Select the a sequence from the Sequence List.

13. Click **Run** to run the selected sequence. Alternatively, you can click **Loop** to continuously run the selection. Click **Halt** to initiate a stop command.

Programming the Control Panel

You can customize the buttons on the control panel by designating default or custom action sequences. Before starting make sure you have already defined any custom sequences, see *"Sequence Editor"* on page 23.

1. Open XYZrobot Editor.

2. Select **Tool** > **Control editor**. The control editor screen displays.

3. In the **Music path** field, click **Search** to select the source directory for audio source. Only WAV formats are supported.

4. From the **Action list**, click the drop-down menu to select a library view type, options include: All/Default/Custom.

    *   All: displays the full listing of default and custom entries.
    *   Default: displays predefined sequences. Entries are defined with a D_ prefix and can not be customized.
    *   Custom: display the user-creaed entries. These entries can be modified.

5. Select an action number and click the drop-down menu to modify.

6. Scroll through the Action list library and select the list entry which will correspond to this action list entry.

7. Select an audio file to customize to this action item. Click the Music drop-down menu and select an available audio file.

Repeat this step for remaining action entries to define.

Once the action entries are defined, you can continue to the remote control settings.

8. Select a button from the Remote control setting and click on the drop-down menu.

9. From the drop-down menu, select an action number, which corresponds to the Action list, to customize the selected button.

Repeat for any remaining buttons.

In this way, the control panel buttons can be customized for defined action items.

Programming the Remote Control

You can customize the buttons on the remote control by designating default or custom action sequences. Before starting, make sure you have already defined any custom sequences; see *"Sequence Editor"* on page 23.

1. Open XYZrobot Editor.

2. Select **Tool** > **Control editor**. The control editor screen displays.

3. In the **Music path** field, click **Search** to select the source directory for audio source. Only WAV formats are supported.

4. From the **Action list**, click the drop-down menu to select a library view type, options include: All/Default/Custom.

   - All: displays the full listing of default and custom entries.
   - Default: displays predefined sequences. Entries are defined with a D_ prefix and can not be customized.
   - Custom: display the user-creaed entries. These entries can be modified.

5. Select an action number and click the drop-down menu to modify.

6. Scroll through the Action list library and select the list entry which will correspond to this action list entry.

7. Select an audio file to customize to this action item. Click the Music drop-down menu and select an available audio file.

Repeat this step for remaining action entries to define.

Once the action entries are defined, you can continue to the remote control settings.

8. Select a button from the Remote control setting and click on the drop-down menu.

9. From the drop-down menu, select an action number, which corresponds to the Action list, to customized the selected button.

Repeat for any remaining buttons.

In this way, the remote control buttons can be customized for defined action items.

Operations

Creating an AVR Format

After customizing control panel buttons or remote control, select **Tool > Export to AVR** to save a .h file for Arduino.

The exporting function allows you to compile the sequenced information into a compiled AVR file, which turns the information into readable Arduino code.

The file can be uploaded to the Arduino software library for editing, see *"Installing Bolide Crawler Default Firmware"* on page 31.

NOTE: To avoid compiler errors, do not change the exported file name (CRAWLER_USER_MOTION.h).

Installing Bolide Crawler Default Firmware

Once the Bolide Crawler firmware is uploaded to the Bolide Crawler board, refer to the following section to continue configuring your device.

1. Connect the Bolide Crawler and computer with a USB cable.
2. Power up the Bolide Crawler; see "Testing the Bolide Crawler" in the Assembly Manual.
3. Locate the Firmware and navigate to the following folder:

    Bolide_Y-01_Arduino_Support_File_20151201\Bolide_Y-01_Default (For the latest software visit http://www.xyzrobot.com)
4. Double click **Bolide_Y-01_Default.ino** to run the application.

5.	From the menu toolbar, click **Tools > Board** and select the option **XYZrobot-BOLIDE**.

6.	Next, select the COM port associated with the Bolide Crawler. From the menu toolbar, click **Tools > Serial Port** and select the associated option.

	NOTE: If the device is not detected, the USB driver may not be recognized. The option to select the associated COM port will not be available. You will need to update or re-install the serial port drivers, see *"USB Drivers"* on page 39.

7.	Click ![verify] (Verify) to compile the codes.

	After compiling, the message **Done compiling** displays at the bottom of the frame.

	If there are no errors and the compiling is complete, upload the code to the MCU board.

8.	Click ![upload] (Upload) to upload the codes.

	After uploading, the message **Done uploading** displays at the bottom of the frame. The Bolide Crawler returns to the default position and an audible alert sounds, indicating a successful upload.
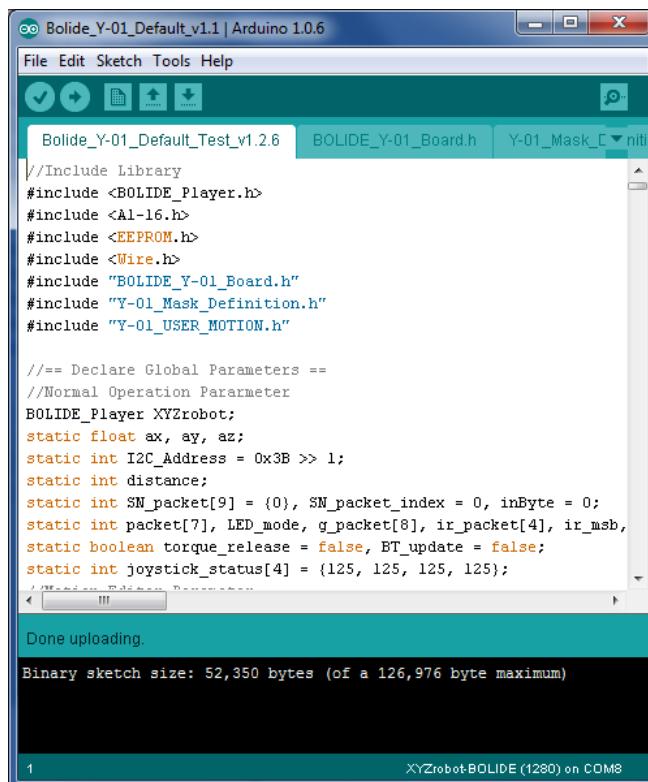
Validating Environment Setup

Once the software is installed and the driver code is uploaded to the Bolide Crawler, validating a successful upload is easy.

The resulting code upload will:

- Return the Bolide Crawler to the default position
- An audible alert sounds indicating a successful completion of the update process.

Operations

External Applications

Introduction

Controlling your Bolide Crawler is not limited to the remote control or the control panel. XYZprinting Inc. has designed and made available an APP for smart devices, making it possible for you to enjoy full control of your Bolide Crawler. The APP is available on iOS and Android. To download your respective app, in Google Play or the APP Store use the keyword XYZrobot to locate and download the latest Bolide Crawler application. To get further information on the user interface, control functions and programming, download the Bolide Crawler APP user manual found on the XYZprinting Inc. website, available here: http://www.xyzrobot.com.

Additional Components

Adapters

Power cables may vary depending on regional requirements.

MicroSD Card

The Bolide Crawler includes a single microSD slot. You can save audio files to a microSD card and insert into the slot. The function buttons can be programmed to trigger an audio file on the microSD card.

Mechanical Components

Hardware Installation

Installing the MicroSD Card

The following microSD card types are supported:

- microSD card
- microSDHC card

1. Locate the microSD slot on the Bolide Crawler.

2. Hold the microSD card with the arrow pointing towards the slot, and carefully slide into the slot until it clicks in place.

⚠ **CAUTION:**

Do not force a microSD card into the slot. Orient the microSD card prior to insertion. Forcing a microSD card into the slot may cause damage to the slot and the microSD card.
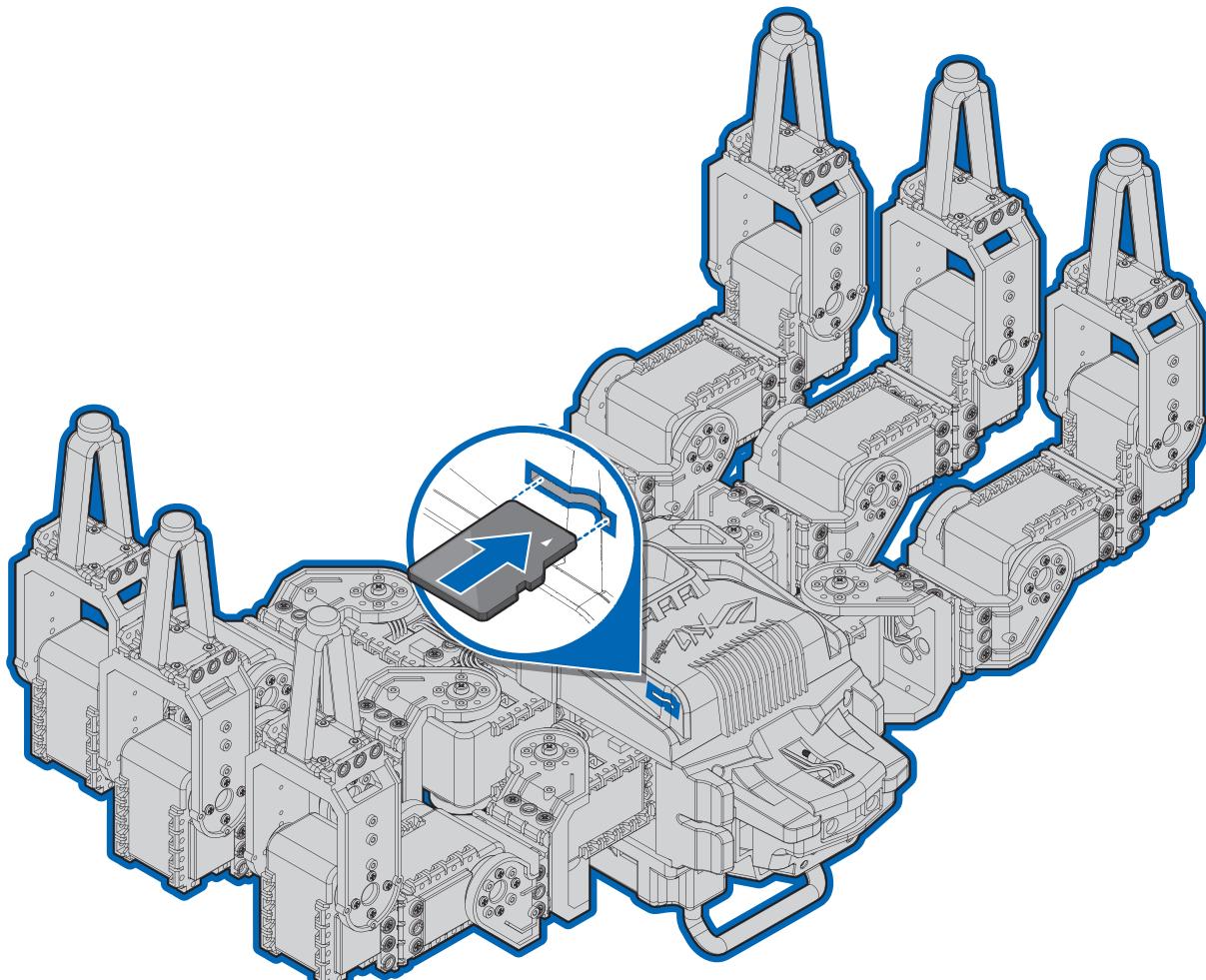
Control Panel

The control panel consists of the power switch button along with four function buttons found just above the battery; see the following illustration.

The function buttons are pre-programmed for a specific action. They can also be manually programmed for personalized preferences.

1. Power switch
2. Function button 1
3. Function button 2
4. Function button 3
5. Function button 4
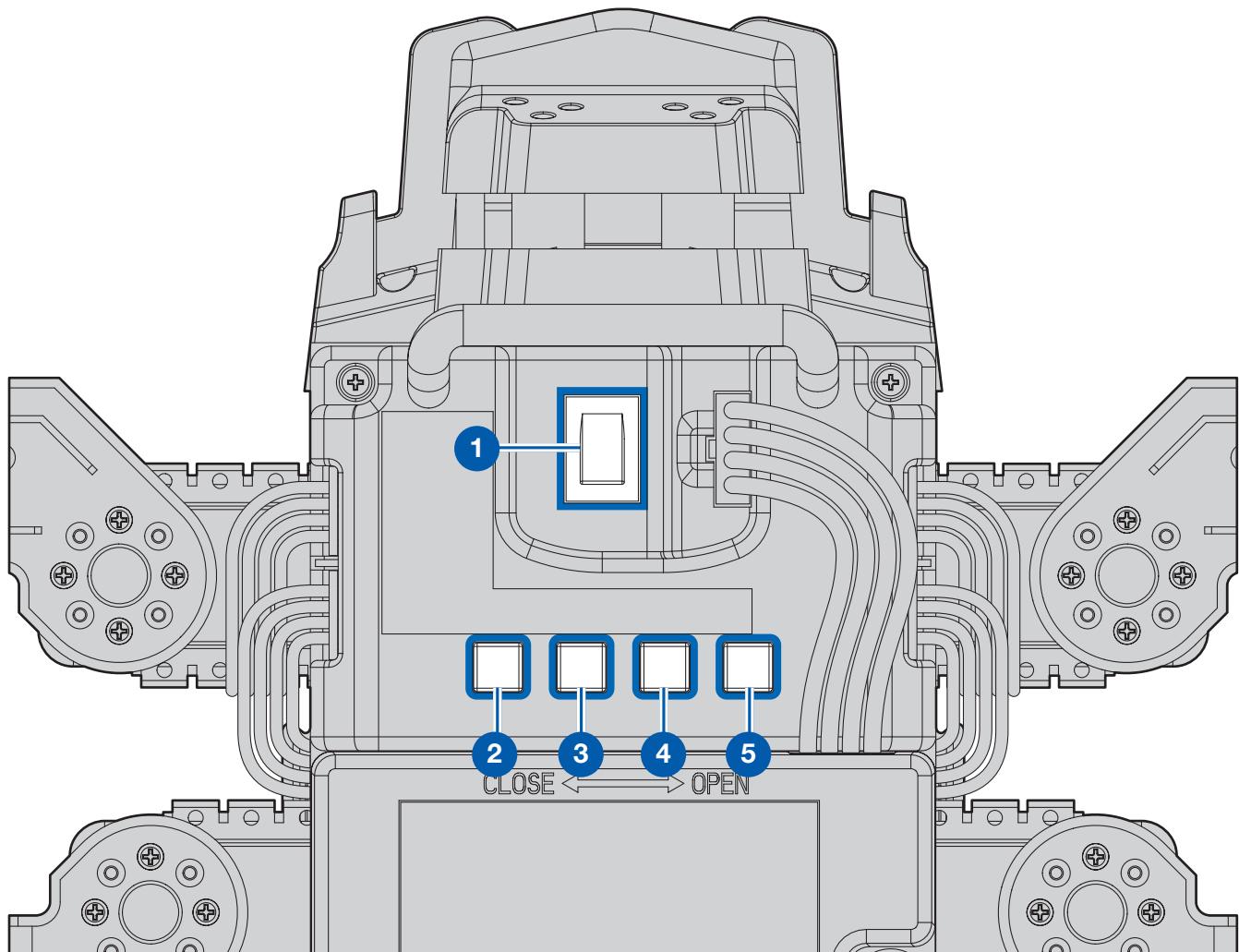
Mechanical Components

Remote Control

The following figure illustrates the default settings pre-programmed on the remote control. To customize the remote control see **"Programming the Remote Control"** *on page 30.*

1. Locking dance
2. Waving
3. Take a bow
4. Hit (up)
5. Turn right
6. Hit (low)
7. Turn left
8. Transmit LED
9. Bluetooth LED
10. Receive LED

11. Bluetooth connect
12. Power
13. Emergency release
14. Walk forward
15. Right
16. Walk backward
17. Left
18. Salute
19. Push up
20. Kung Fu fighting
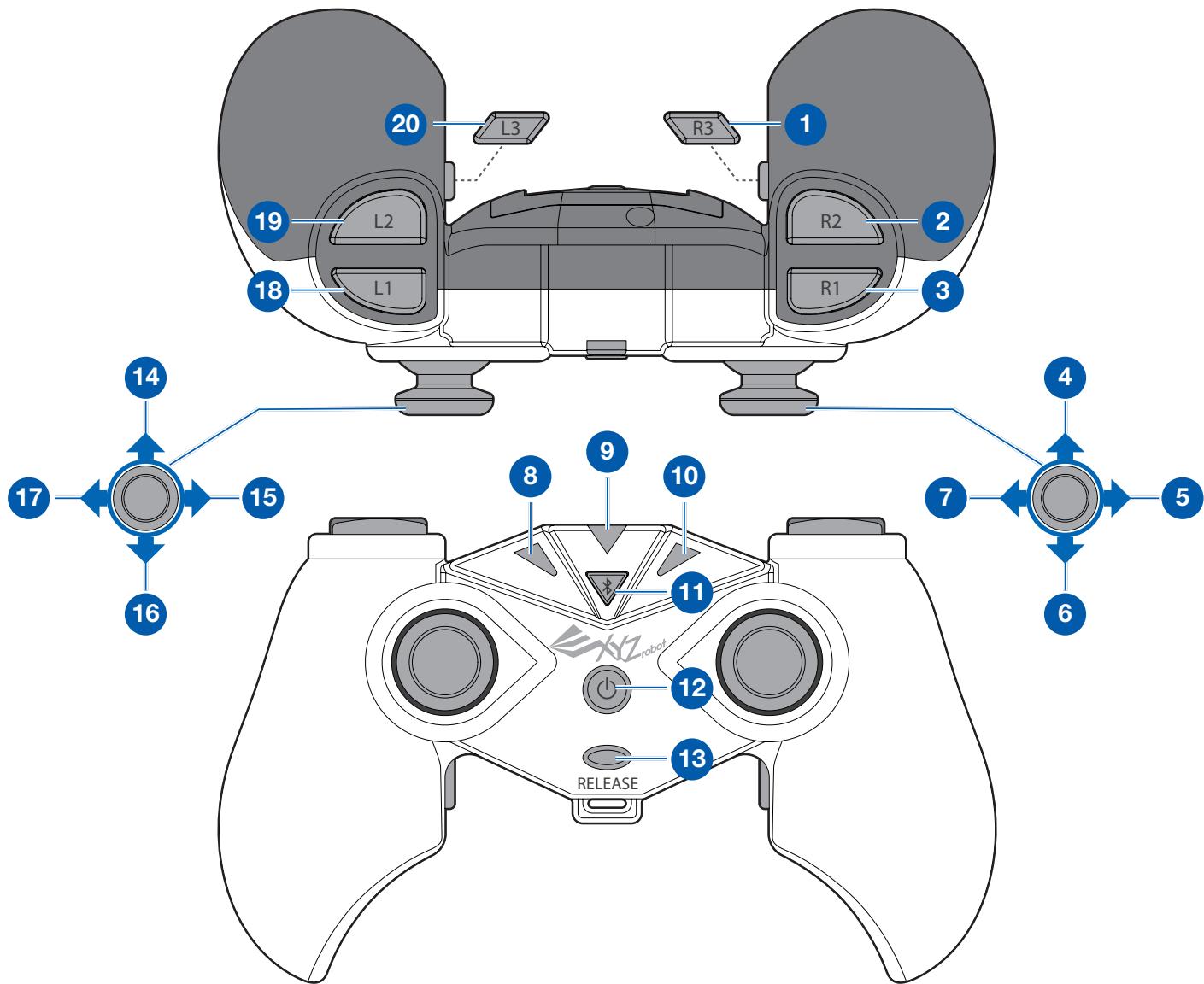
LED Codes

Definition List

For the LED position, please refer to the Bolide Crawler Assembly Manual.

Eye LED

The LEDs located on the eye sockets indicate the following states:

- Power on: sequentially blinks red, green and blue.
- Connection to remote control: sequentially blinks red, green and blue.

Chest LED

Power on/control: LED blinks in sequence (Red, Green and Blue).

Remote Control LED

Transmit LED	Bluetooth LED	Receive LED	Description
LED on (Red)	LED on (Red)	LED on (Red)	Power on
LED on (Green)	LED off	LED on (Green)	Unconnected
LED on (Green)	LED on (Red)	LED on (Green)	Pairing
LED on (Red)	LED on (Blue)	LED on (Green)	Connected (Data transmitted)
LED on (Green)	LED on (Blue)	LED on (Red)	Connected (Data received)
LED on (Orange)	LED on (Blue)	LED on (Orange)	Press power button

Smart Servo LED

Status Error	Error LED on/off
Normal Operation	LED on (White)
Exceed Potentiometer Range Error	LED on (Blue)
Over Voltage/Temperature/Current Limits Error	LED on (Red) LED off (White)
Requested Packet Error	LED on (Green)

Maintenance

USB Drivers

Installing a USB FTDI Driver

The USB driver may require updating or re-installing when the Bolide Crawler device is not recognized by your operating system. The following section provides step-by-step instructions of the installation procedure on a Windows operating system.

1. Download the driver file and extract it to your hard drive, somewhere you can find it.
2. You first need to uninstall the incorrect drivers on your computer. In Windows, go to **Control Panel** then to **Device Manager**.
3. Select **Ports (COM & LPT)** to expand the port list.
4. Select the USB Serial Port associated with the Bolide Crawler device.
5. Right click on the selection and select **Uninstall** from the pop-up window.
6. A confirmation window appears, check the **Delete the driver software for this device** option and click **OK** to complete the uninstallation process.
7. From the Device Manager window, click **Universal Serial Bus Controllers** to expand the list.
8. You will need to uninstall the existing USB Serial Converter. To do this, scroll down the list and select USB Serial Converter and right click to open a pop-up menu.
9. From the menu selections, click **Uninstall**.
10. If the Bolide Crawler device is connected to your computer through the USB cable at this time, disconnect the USB cable.
11. Turn on the Bolide Crawler if it isn't powered on already. Then re-connect the USB cable from the Bolide Crawler to a USB port on your system.

    The operating system detects the new USB connection. In the Device Manager, a new Flagged item appears under Other Devices.
12. Right click on the detected device and right-click on it to open up the Properties menu.
13. From the menu, select **Update Driver Software**.
14. An Update Driver Software window displays. Click **Browse** to navigate to the previously saved driver files on your computer.
15. Select the file and tick the **Include subfolders** option, then click **Next** to continue.
16. Click **Close** to finish this step.

    The USB Serial Converter drivers are now installed. Next you will need to install the Port driver.
17. In the Other Devices list item, the selection is now changed to USB Serial Port. Select this item and right-click to open up the Properties window.
18. Select **Update Driver Software**.
19. The Update Driver Software window displays. Click **Browse** to select the driver file, located in the same location as the previous file.
20. Select the file and tick the **Include subfolders** option, then click **Next** to continue.
21. Click **Close** to complete the Port driver installation.

Both drivers are now installed. The Bolide Crawler is available for selection through the COM port by both the Adruino software and the XYZrobot Editor.

I can't connect my robot to the PC.

1. Open Device Manager on Windows.

When the product is connected to the PC, please check whether the connected device's port is found.

2. If the port is not detected, you may need to install an FTDI serial driver.

If you have problems with other products, or can't solve the problem with the instructions above, please contact your regional manager.

The Arduino displays "Done uploading" but still displays an error message the burn program process.

```
Done uploading.

Binary sketch size: 61,102 bytes (of a 126,976 byte maximum)
avrdude: stk500_getsync(): not in sync: resp=0x00
```

1. Possible cause: low power.

Please charge the Li-ion battery fully or connect the adaptor and try again.

2. Possible cause: the selected COM port is wrong.

Select **Config > Port Setting**. Select the currently connected COM port and click **OK**.

ENGLISH	繁體中文	简体中文	日本語
About	關於 XYZrobot 動作編輯器	关于 XYZrobot 动作编辑器	XYZrobotモーション編集ソフトについて
Founded in 2013, XYZprinting is dedicated to bringing cost-effective 3D printing to personnel and businesses around the world. With proven industry expertise, an innovative spirit, and backing by the world's leading electronic manufacturing conglomerate, Kinpo Group, XYZrobot was founded in 2015. A realization of the innovative spirit came in the form of the Y-01 Bolide robot. The Bolide is designed to bring previously prohibitive robotic solutions to a wider audience with cost effective kits. This unique DIY engineering learning kit is specifically intended to enhance STEAM education to meet engaging and entertaining objectives. With the Bolide, users can adjust and configure each smart servo to create varying poses and sequences. Customized settings can be saved through the XYZrobot Editor software available for Windows and Mac OS systems. The XYZrobot Editor is compatible with the Arduino (v1.0.6) open source software allowing users to share an programming development environment. Users can create customized movement sequences and share through the XYZrobot app for both Android and Apple devices.	XYZprinting 三緯國際立體列印科技(股)，專注於研發、設計及製造3D列印機。三緯國際以「全球佈局，在地深耕」的策略，從台灣到立足大中華區，由亞洲擴展至歐美，陸續在日本、美國及歐洲等當地設立XYZprinting分公司，更在2015年成立XYZrobot，致力於科技創新，期望每次的起步帶給人類生活的便利，不管是印表機或是機器人皆是未來生活中不可或缺的新工具。Y-01 火流星擁有18個自由度，可以做式各樣的動作，透過XYZrobot 編輯器，你可以自行設計動作並串成一連串的舞蹈動作、武打動作，想怎麼動就怎麼動。使用 Arduino 1.0.6 和XYZrobot編輯器(支援Windows 和 Mac iOS)，編輯好即可存取至遙控器或是APP，你的機器人，由你做主。	XYZprinting 三纬国际立体列印科技(股)，专注于研发、设计及制造3D列印机。三纬国际以「全球布局，在地深耕」的策略，从台湾到立足大中华区，由亚洲扩展至欧美，陆续在日本、美国及欧洲等当地设立XYZprinting分公司，更在2015年成立XYZrobot，致力于科技创新，期望每次的起步带给人类生活的便利，不管是印表机或是机器人皆是未来生活中不可或缺的新工具。Y-01 火流星拥有18个自由度，可以做各式各样的动作，透过XYZrobot 编辑器，你可以自行设计动作并串成一连串的舞蹈动作、武打动作，想怎么动就怎么动。使用 Arduino 1.0.6 和XYZrobot编辑器(支援Windows 和 Mac iOS)，编辑好即可存取至遥控器或是APP，你的机器人，由你做主。	XYZプリンティングは3Dプリンタの研究開発、設計、製造を専門に行う企業です。「グローバル化」戦略のもと、本社を置く台湾から中華圏を足がかりにアジアから欧米までビジネスを展開し、日本、米国、欧州等の国々で次々と子会社を設立しています。2015年にはXYZrobotを設立して科学技術の発展により一層注力し、当社が人々の生活の利便性向上に貢献できることを願っています。3Dプリンタもロボットもこれからの生活においてなくてはならない新たなツールです。Y-01 BOLIDEは18の自由度をもち、さまざまな動作を行うことができます。XYZrobotモーション編集ソフトを使ってオリジナルの動作をデザインすることで、一連のダンスアクションやバトルアクションなど、自由自在に動かせます。
Action list	操作列表	操作列表	動作リスト
Action No.	操作號碼	操作号码	動作番号
Add	新增	新增	追加
Add	加入	加入	追加する
Alert	警告	警告	警告
Cancel	取消	取消	キャンセル
Capture	擷取	撷取	キャプチャー
Close	關閉程式	关闭程式	終了する
Close window	關閉視窗	关闭视窗	ウィンドウを閉じる
Connection to {0}	連線到 {0}	连线到 {0}	{0} に接続する
Config	偏好設定	偏好设定	設定
Confirm	確認	确认	確認
Connecting ...	連線中...	连线中...	接続しています...
Connection timed out. Ensure power is turned on.	連線逾時,請確認電源是否開啟	连线逾时,请确认电源是否开启	接続は、電源がオンになっていることを確認してください
Control editor	控制編輯	控制编辑	コントロール編集
Create new project	建立新專案	建立新专案	新しいプロジェクトを作成する
Delay	延遲	延迟	遅延
Delete	刪除	删除	削除
Are you sure you want to delete?	請再次確認是否要刪除該項目？	请再次确认是否要删除该项目？	このポーズを本当に削除しますか？
Delay	持續時間	持续时间	持続時間
Down	下	下	ダウン

ENGLISH	繁體中文	简体中文	日本語
Edit pose	編輯動作	编辑动作	ポーズを編集
Edit sequence	編輯連續動作	编辑连续动作	モーションを編集
Create failed. Duplicate name.	建立失敗, 名稱重覆!!	建立失败, 名称重覆!!	作成できませんでした。同じ名称のプロジェクトが存在しています！！
Import failed. Duplicate name.	匯入失敗!! 動作名稱重複~	汇入失败!! 动作名称重复~	未完成インポートするアクション名を繰り返します
Can't open file.	導入專案內容格式或機型不符，無法使用	导入项目内容格式或机型不符，无法使用	ファイルを開けません
Error	錯誤	错误	エラー
Exit	關閉程式	关闭程式	終了する
Can't export file	無法匯出檔案	无法汇出档案	ファイルをエクスポートできません
Export to AVR	匯出至 AVR	汇出至 AVR	AVRソースファイルにエクスポートする
Do you want to save changes before closing?	關閉前是否要儲存現有的變更?	关闭前是否要储存现有的变更?	終了する前に変更された内容を保存しますか？
Halt	中斷	中断	中断
Help	說明	说明	説明
Import	匯入	汇入	インポート
L1	L1	L1	L1
L2	L2	L2	L2
L3	L3	L3	L3
Left	左	左	左
Left arm	左臂	左臂	左腕
Left back leg	左後足	左后足	左後脚
Left front leg	左前足	左前足	左前脚
Left leg	左腿	左腿	左脚
Left middle leg	左中足	左中足	左中脚
Live pose update	同步ROBOT動作	同步ROBOT动作	ロボットのポーズを同期
Loading...	Loading...	Loading...	Loading...
Loop	迴圈	回圈	ループ
Maximize window	最大化視窗	最大化视窗	ウィンドウを最大化する
Minimize window	最小化視窗	最小化视窗	ウィンドウを最小化する
Model	機種	机种	モデル
Model does not match.	匯入檔的機型與目前專案不相符	汇入档的机型与目前专案不相符	インポートプロファイルモデルは、現在のプロジェクトと一致しません
Editor v2.0	動作編輯器 v2.0	动作编辑器 v2.0	編集ソフト v2.0
Move down	下移	下移	下へ移動する
Move up	上移	上移	上へ移動する
(ms)	(毫秒)	(毫秒)	(ミリ秒)
A file with the same name already exists in the folder. Current contents will be overwritten if file is replaced.	檔案夾裡已經有名稱相同的檔案。若選擇取代，將會覆寫原有的內容。	档案夹里已经有名称相同的档案。若选择取代,将会覆写原有的内容。	同じ名前のファイルが既に存在します。これを置き換えると現在の内容が上書きされます。
already exists. Do you want to replace it?	已存在。要取代嗎?	已存在。要取代吗?	はすでに存在しています。置き換えてもよろしいですか？
No default pose. Add a pose and define it as default.	尚有default未指定pose，請先進行該項設定後再新增。	尚有default未指定pose，請先進行該項設定後再新增。	尚有default未指定pose，請先進行該項設定後再新增。
No default pose. Unable to complete command. Define a default pose.	尚有default未指定pose，無法執行動作指令，請先進行該項設定。	尚有default未指定pose，無法執行動作指令，請先進行該項設定。	尚有default未指定pose，無法執行動作指令，請先進行該項設定。
There is an unspecified pose in the sequence {0}. Assign the pose in Sequence editor page before exporting AVR file.	連續動作({0})中存在未指定的動作名稱，請先於 [連續動作編輯] 頁面進行該項設定後再匯出。	连续动作({0})中存在未指定的动作名称，请先于 [连续动作编辑] 页面进行该项设定后再汇出。	There is an unspecified pose in the sequence {0}. Assign the pose in Sequence editor page before exporting AVR file.

ENGLISH	繁體中文	简体中文	日本語
Export failed. AVR file too large.	匯出AVR的容量過大, 匯出失敗	匯出AVR的容量過大, 匯出失敗	匯出AVR的容量過大, 匯出失敗
Invalid naming. Name cannot start with D_ or E_ designation.	"請勿使用關鍵字(default)，且不可使用特殊字元(D_ 或 E_)與數字為開頭，名稱最少含兩個字元"	命名开头不可使用关键字(D_ or E_)	キーワードで始まる名前を使用しないでくださ-い(D_ or E_)
Enter project name.	請輸入專案名稱	请输入专案名称	プロジェクト名を入力してください
Music	音樂	音乐	音楽
Music path	音樂路徑	音乐路径	音楽パス
Name	名稱	名称	プロジェクト名
Duplicate name exists	名稱已存在	名称已存在	同じ名称のプロジェクトが既に存在しています
Sequence name cannot be the same as pose name.	連續動作名稱與動作名稱不可相同	连续动作名称与动作名称不可相同	モーション名はポーズ名と異なるものにしてください
Pose name cannot be the same as sequence name.	動作名稱與連續動作名稱不可相同	动作名称与连续动作名称不可相同	ポーズ名はモーション名と異なるものにしてください
Does not meet naming convention requirement.	不符合命名規範	不符合命名规范	名称が命名規則に合致しません
Cannot begin with a number or use special characters. Minimum of two characters.	請勿以數字開頭, 且不可使用特殊字元(D_,E_), 名稱最少兩個字元	请勿以数字开头, 且不可使用特殊字元, 名称最少两个字元	最初の文字に数字を使用したり、特殊文字を使用したりせず、名称は2文字以上にしてください
New	新專案	新专案	新しいプロジェクト
New pose settings	建立新動作設定檔	建立新动作设定档	新しいポーズを設定する
New sequence settings	建立新連續動作設定檔	建立新连续动作设定档	新しいモーションを設定する
No	否	否	いいえ
Not connected	未連線	未连线	未接続
Now editing pose: {0}	正在編輯動作: {0}	正在编辑动作: {0}	編集中のポーズ：{0}
Now editing sequence: {0}	正在編輯連續動作: {0}	正在编辑连续动作: {0}	編集中のモーション：{0}
Now selecting sequence: {0}	正在選取連續動作: {0}	正在选取连续动作: {0}	Now selecting sequence: {0}
Ok	確認	确认	確認
Open	開啟專案	开启专案	プロジェクトを開く
Parameters	參數	参数	設定値
First, create a new robot.	請先建立Robot新專案或載入現有Robot專案	请先建立Robot新专案或载入现有Robot专案	先にRobotの新しいプロジェクトを作成するか、既存のRobotプロジェクトをロードしてください
First, create a pose name.	請先建立一個動作名稱	请先建立一个动作名称	先にポーズ名を決定してください
First, create a sequence name.	請先新增一個連續動作名稱	请先新增一个连续动作名称	先にモーション名を決定してください
Create or select a sequence to edit.	請先建立連續動作或選擇現有的連續動作	请先建立连续动作或选择现有的连续动作	先にモーションを作成するか、既存のモーションを選択してください
Select a pose to edit.	請先選擇動作, 再進行相關的編輯	请先选择动作, 再进行相关的编辑	先にポーズを選択してから関連する編集を行ってください
Select a sequence to edit.	請先選擇連續動作, 再進行相關的編輯	请先选择连续动作, 再进行相关的编辑	先にモーションを選択してから関連する編集を行ってください
Port	埠號	埠号	ポート
Port (Ex. COM1, dev, ttyUSB0)	序列埠號 (例如. COM1 or /dev/ttyUSB0)	埠号 (例如. COM1 or /dev/ttyUSB0)	ポート (例：COM1 or /dev/ttyUSB0)
Port setting	序列埠設定	序列埠设定	シリアルポート設定
Pose	動作	动作	ポーズ
Pose editor	動作編輯	动作编辑	ポーズの編集
Pose list	動作列表	动作列表	ポーズリスト
Pose name	動作名稱	动作名称	ポーズ名
Project	專案	专案	プロジェクト
Project:{0} unmatched condition	專案:{0} 名稱不符合規範	专案:{0} 名称不符合规范	プロジェクト：{0} 名称が命名規則に合致しません

ENGLISH	繁體中文	简体中文	日本語
Project name	專案名稱	专案名称	プロジェクト名
R1	R1	R1	R1
R2	R2	R2	R2
R3	R3	R3	R3
Relax	放鬆	放松	脱力
Remote control setting	遙控器設定	遥控器设定	リモートコントロール設定
Remove	刪除	删除	削除
Rename	更名	更名	名称変更
Rename pose	重新命名	重新命名	ポーズ名を変更する
Rename sequence	重新命名	重新命名	モーション名を変更する
Right	右	右	右
Right arm	右臂	右臂	右腕
Right back leg	右後足	右后足	右後脚
Right front leg	右前足	右前足	右前脚
Right leg	右腿	右腿	右脚
Right middle leg	右中足	右中足	右中脚
XYZrobot	XYZrobot	XYZrobot	XYZrobot
Button 1	按鈕1	按钮1	ボタン1
Button 2	按鈕2	按钮2	ボタン2
Button 3	按鈕3	按钮3	ボタン3
Button 4	按鈕4	按钮4	ボタン4
Robot button setting	機器人控制鈕設定	机器人控制钮设定	ロボット　ボタン設定
Run	執行	执行	実行
Sample player	採樣播放器	采样播放器	サンプル　プレーヤ
Sample pose	採樣動作	採樣动作	サンプル ポーズ
Sample sequence	採樣連續動作	採樣连续动作	サンプル モーション
Save	儲存專案	储存专案	プロジェクトを保存する
Save As	另存專案	另存专案	別の名前でプロジェクトを保存する
Save complete	儲存完畢	储存完毕	保存完了
Search	搜尋	搜索	サーチ
Select communications port	選擇通訊用COM埠號	选择通讯用COM埠号	通信用シリアルポートを選択する
Sequence editor	連續動作編輯	连续动作编辑	モーションの編集
Sequence list	連續動作列表	连续动作列表	モーションリスト
Sequence name	連續動作名稱	连续动作名称	モーション名
Serial port initialization start...	序列埠正在初始化	序列埠正在初始化	すべてのシリアル・ポートが初期化されます
Serial number	序號	序号	シリアル番号
# of servos	馬達數量	马达数量	サーボモーター数
Set	設定	设定	設定
XYZrobot Editor V1.0	XYZrobot 編輯器 V1.0	XYZrobot 编辑器 V1.0	XYZrobotモーション編集ソフトV1.0
Tool	工具	工具	ツール
Transitions	動作清單	动作清单	操作一覧
Up	上	上	アップ
Warning	警示	警示	警告
Yes	是	是	はい

ENGLISH	ITALIANO	FRANÇAIS
Founded in 2013, XYZprinting is dedicated to bringing cost-effective 3D printing to personnel and businesses around the world. With proven industry expertise, an innovative spirit, and backing by the world's leading electronic manufacturing conglomerate, Kinpo Group, XYZrobot was founded in 2015. A realization of the innovative spirit came in the form of the Y-01 Bolide robot. The Bolide is designed to bring previously prohibitive robotic solutions to a wider audience with cost effective kits. This unique DIY engineering learning kit is specifically intended to enhance STEAM education to meet engaging and entertaining objectives. With the Bolide, users can adjust and configure each smart servo to create varying poses and sequences. Customized settings can be saved through the XYZrobot Editor software available for Windows and Mac OS systems. The XYZrobot Editor is compatible with the Arduino (v1.0.6) open source software allowing users to share an programming development environment. Users can create customized movement sequences and share through the XYZrobot app for both Android and Apple devices.	Fondata nel 2013, XYZprinting ha l'obiettivo di diffondere la stampa 3D economica tra i privati e le aziende di tutto il mondo. XYZrobot è stata fondata nel 2015 con una comprovata esperienza nel settore, uno spirito innovativo e il sostegno da parte di Kinpo Group, un gruppo leader mondiale nella produzione di componenti elettronici. Una concretizzazione dello spirito innovativo ha dato vita al robot Y-01 Bolide. Il Bolide è progettato per estendere a un pubblico più vasto soluzioni in precedenza economicamente proibitive attraverso un kit dal costo più abbordabile. Questo kit di apprendimento ingegneristico fai da te unico è specificatamente destinato a migliorare l'istruzione STEAM (Science, Technology, Engineering, Arts and Mathematics) attraverso il raggiungimento di obiettivi coinvolgenti e divertenti. Con il Bolide, gli utenti possono regolare e configurare ogni servomotore intelligente per creare pose e sequenze diverse. Le impostazioni personalizzate possono essere salvate attraverso l'applicazione XYZrobot Editor disponibile per i sistemi Windows e Mac OS. XYZrobot Editor è compatibile con il software open source Arduino (v1.0.6) permettendo agli utenti di condividere l'ambiente di sviluppo del codice. Gli utenti possono creare sequenze di movimenti personalizzati e condividerli attraverso l'applicazione XYZrobot disponibile per i dispositivi Android e Apple.	Créée en 2013, la société XYZprinting a pour mission de fournir de l'impression 3D à un coût compétitif aux personnes et aux entreprises du monde entier. Grâce à son expertise industrielle reconnue, son esprit innovant et le soutien du grand groupe industriel Kinpo, leader mondial dans la fabrication de produits électroniques, la société XYZrobot a été créée en 2015. Une première réalisation issue de cet esprit innovant est incarnée par le robot Y-01 Bolide. Le Bolide a été conçu pour permettre à un plus large public d'accéder à des solutions robotiques jusqu'alors prohibitives grâce à des kits à coûts compétitifs. Ce kit pour apprentis ingénieurs, à monter soi-même, est conçu tout particulièrement pour contribuer à une éducation STEAM afin d'atteindre des objectifs stimulants et amusants. Avec le Bolide, les utilisateurs peuvent ajuster et configurer chaque servomoteur intelligent pour créer différentes poses et séquences. Les paramètres personnalisés peuvent être sauvegardés grâce au logiciel XYZrobot Editor disponible en version Windows et Mac OS. ZYZrobot Editor est compatible avec le logiciel open source Arduino (v1.0.6) permettant ainsi aux utilisateurs de partager un même environnement de programmation. Les utilisateurs peuvent créer des séquences de mouvements personnalisées et les partager par l'intermédiaire de l'appli XYZrobot sur appareils Androïd ou Apple.
About	Su	Sur
Action list	Elenco azioni	Liste d'actions
Action No.	Azione n.	Action n°
Add	aggiungere	Ajouter
Add	Aggiungi Posa	Ajouter une pose
Alert	allertare	alerter
Cancel	Annulla	Annuler
Capture	Acquisisci	Capture
Close	Chiudi	Fermer
Close window	Chiudi finestra	Fermer la fenêtre
Connection to {0}	Collegamento a {0}	Connexion à {0}
Config	Config	Config
Confirm	confermare	confirmer
Connecting ...	Connessione in corso...	Connexion en cours…
Connection timed out. Ensure power is turned on.	Connessione scaduta. Assicurarsi che l'interruttore sia acceso.	Échec de la connexion. Assurez-vous que l'alimentation est branchée.
Control editor	Editor controlli	Éditeur de contrôle
Create new project	Crea un nuovo progetto	Créer un nouveau projet
Delay	ritardo	retarder
Delete	cancellare	effacer
Are you sure you want to delete?	Sei sicuro di volerlo cancellare?	Êtes-vous sûr de vouloir supprimer?
Delay	durata	durée
Down	giù	le bas
Edit pose	Modifica posa	Modifier la pose
Edit sequence	Modifica sequenza	Modifier la séquence

07 Appendix
Italiano | Français

ENGLISH	ITALIANO	FRANÇAIS
Create failed. Duplicate name.	Creazione fallita. Nome duplicato.	Échec de la création. Nom en double.
Import failed. Duplicate name.	Importazione non riuscita. Nome duplicato.	Échec de l'importation. Nom en double.
Can't open file.	Impossibile aprire il file.	Impossible d'ouvrir le fichier.
Error	errore	erreur
Exit	uscita	sortie
Can't export file	Impossibile esportare il file.	Impossible d'exporter le fichier.
Export to AVR	Esporta in AVR	Exporter vers AVR
Do you want to save changes before closing?	Vuoi salvare le modifiche prima di chiudere?	Sauvegarder les modifications avant de fermer?
Halt	Arresta	Arrêter
Help	Aiuto	Aider
Import	Importazione	importer
L1	L1	L1
L2	L2	L2
L3	L3	L3
Left	sinistra	gauche
Left arm	Braccio sinistro	bras gauche
Left back leg	Gamba posteriore sinistra	Jambe arrière gauche
Left front leg	Gamba anteriore sinistra	Jambe avant gauche
Left leg	Gamba sinistra	Jambe gauche
Left middle leg	Gamba centrale sinistra	Jambe centrale gauche
Live pose update	Aggiornamento posa in tempo reale	Mise à jour de la pose en temps réel
Loading...	Caricamento in corso…	Chargement en cours...
Loop	Ciclo	Boucle
Maximize window	Massimizza finestra	Agrandir fenêtre au maximum
Minimize window	Minimizza finestra	Réduire fenêtre au minimum
Model	modello	modèle
Model does not match.	Il modello non corrisponde.	Le modèle ne convient pas.
Editor v2.0	Editor v2.0	Éditeur v2.0
Move down	Sposta giù	Se déplacer vers le bas
Move up	Sposta su	Se déplacer vers le haut
(ms)	(ms)	(ms)
A file with the same name already exists in the folder. Current contents will be overwritten if file is replaced.	Un file con lo stesso nome è già presente nella cartella. Il contenuto corrente sarà sovrascritto se il file viene sostituito.	Un fichier portant le même nom existe déjà dans le dossier. Le contenu actuel sera écrasé si vous remplacez le fichier.
already exists. Do you want to replace it?	Già esistente. Vuoi sostituirlo?	Existe déjà. Voulez-vous le remplacer ?
No default pose. Add a pose and define it as default.	Nessuna posa predefinita. Aggiungi una posa e impostala come predefinita.	Pas de pose par défaut. Ajoutez une pose et définissez-le comme la pose par défaut.
No default pose. Unable to complete command. Define a default pose.	Impossibile completare il comando. Definisci una posa predefinita.	Impossible de terminer la commande. Définissez une pose par défaut.
There is an unspecified pose in the sequence {0}. Assign the pose in Sequence editor page before exporting AVR file.	C'è una posa non specificata nella sequenza {0}. Assegna la posa nella pagina dell'editor delle sequenze prima di esportare file AVR.	Il y a une pose non définie dans la séquence {0}. Définissez la pose dans la page d'édition de la séquence avant d'exporter le fichier AVR.
Export failed. AVR file too large.	Esportazione non riuscita. File AVR troppo grande.	Échec de l'exportation. Fichier AVR trop gros.
Invalid naming. Name cannot start with D_ or E_ designation.	Denominazione non valida. Il nome non può iniziare con D_ o E_.	Nom non valide. Le nom ne peut pas démarrer avec les termes D_ ou E_ .
Enter project name.	Inserisci il nome del progetto.	Entrez nom du projet.
Music	musicale	musique
Music path	Percorso musicale	musique

ENGLISH	ITALIANO	FRANÇAIS
Name	nome	nom
Duplicate name exists	Esistono nomi duplicati	Ce nom existe en double
Sequence name cannot be the same as pose name.	Il nome della sequenza non può essere lo stesso della posa.	Le nom de la séquence ne peut pas être le même que celui de la pose.
Pose name cannot be the same as sequence name.	Il nome della posa non può essere lo stesso della sequenza.	Le nom de la pose ne peut pas être le même que celui de la séquence.
Does not meet naming convention requirement.	Non soddisfa i requisiti convenzionali per la denominazione.	N'obéit pas aux conventions de définition des noms.
Cannot begin with a number or use special characters. Minimum of two characters.	Non può iniziare con un numero o utilizzare caratteri speciali. Minimo due caratteri.	Ne peut pas démarrer avec un chiffre, ni utiliser des caractères spéciaux. Deux caractères.
New	nuova	Nouveaux
New pose settings	Impostazioni nuova posa	Nouveaux paramètres de pose
New sequence settings	Impostazioni nuova sequenza	Nouveaux paramètres de séquence
No	no	non
Not connected	Non connesso	Non connecté
Now editing pose: {0}	Posa in corso di modifica: {0}	Modification en cours de la pose: {0}
Now editing sequence: {0}	Sequenza in corso di modifica: {0}	Modification en cours de la séquence: {0}
Now selecting sequence: {0}	Sequenza attualmente selezionata: {0}	Sélection en cours de la séquence: {0}
Ok	Conferma	Confirmer
Open	Apri	Ouvrir
Parameters	Parametro	Paramètre
First, create a new robot.	In primo luogo, crea un nuovo robot.	Créer d'abord un nouveau robot.
First, create a pose name.	In primo luogo, creare un nome di posa.	Créer d'abord un nom de pose.
First, create a sequence name.	In primo luogo, crea un nome di sequenza.	Créer d'abord un nom de séquence.
Create or select a sequence to edit.	Crea o seleziona una sequenza da modificare.	Créer ou sélectionner une séquence à modifier.
Select a pose to edit.	Seleziona una posa da modificare.	Sélectionner une pose à modifier.
Select a sequence to edit.	Seleziona una sequenza da modificare.	Sélectionner une séquence à modifier.
Port	porta	port
Port (Ex. COM1, dev, ttyUSB0)	porta (Es. COM1, dev, ttyUSB0)	port (Par ex. : COM1, dev, ttyUSB0)
Port setting	Impostazione porta	Paramètre de port
Pose	pose	pose
Pose editor	Editore pose	Éditeur de pose
Pose list	Elenco pose	Liste de poses
Pose name	Nome posa	Nom de pose
Project	Progetto	Projet
Project:{0} unmatched condition	Progetto: {0} condizioni non rispettate	Projet : {0} condition non trouvée
Project name	Nome progetto	Nom de projet
R1	R1	R1
R2	R2	R2
R3	R3	R3
Relax	entspannen	détendre
Remote control setting	Impostazioni telecomando	Paramètre de télécommande
Remove	Rimuovere	Supprimer
Rename	Rinomina	Renommer
Rename pose	Rinomina posa	Renommer la pose
Rename sequence	Rinomina sequenza	Renommer la séquence
Right	destra	droit
Right arm	Braccio destra	bras droit
Right back leg	Gamba posteriore destra	Jambe arrière droit

ENGLISH	ITALIANO	FRANÇAIS
Right front leg	Gamba anteriore destra	Jambe avant droit
Right leg	Gamba destra	Jambe droit
Right middle leg	Gamba centrale destra	Jambe centrale droit
XYZrobot	XYZrobot	XYZrobot
Button 1	Pulsante 1	Bouton 1
Button 2	Pulsante 2	Bouton 2
Button 3	Pulsante 3	Bouton 3
Button 4	Pulsante 4	Bouton 4
Robot button setting	Impostazioni pulsante robot	Paramètre de bouton de robot
Run	Esegui	Exécuter
Sample player	Riproduzione esempi	Lecteur d'échantillons
Sample pose	Posa di esempio	Échantillon de pose
Sample sequence	Sequenza di esempio	Échantillon de séquence
Save	Salvare	Garder
Save As	Salva come	Enregistrer sous
Save complete	Salvataggio completo	Sauvegarde effectuée
Search	cercare	chercher
Select communications port	Seleziona porta di comunicazione	Sélectionner le port de communications
Sequence editor	Editor sequenza	Éditeur de séquence
Sequence list	Elenco sequenze	Liste de séquences
Sequence name	Nome sequenza	Début de l'initialisation du port série…
Serial port initialization start...	Avvio inizializzazione porta seriale...	Numéro de série
Serial number	Numero di serie	Nombre de servomoteurs
# of servos	# di servomotori	Nombre de servos
Set	Imposta	Régler
XYZrobot Editor V1.0	XYZrobot Editor	XYZrobot Éditeur
Tool	Utensili	Outils
Transitions	Record	Archives
Up	su	sur
Warning	Avviso	Avertissement
Yes	sì	oui

ENGLISH	ESPAÑOL	DEUTSCHE
About	Sobre	über
Founded in 2013, XYZprinting is dedicated to bringing cost-effective 3D printing to personnel and businesses around the world. With proven industry expertise, an innovative spirit, and backing by the world's leading electronic manufacturing conglomerate, Kinpo Group, XYZrobot was founded in 2015. A realization of the innovative spirit came in the form of the Y-01 Bolide robot. The Bolide is designed to bring previously prohibitive robotic solutions to a wider audience with cost effective kits. This unique DIY engineering learning kit is specifically intended to enhance STEAM education to meet engaging and entertaining objectives. With the Bolide, users can adjust and configure each smart servo to create varying poses and sequences. Customized settings can be saved through the XYZrobot Editor software available for Windows and Mac OS systems. The XYZrobot Editor is compatible with the Arduino (v1.0.6) open source software allowing users to share an programming development environment. Users can create customized movement sequences and share through the XYZrobot app for both Android and Apple devices.	Fundada en 2013, XYZprinting está dedicada a proporcionar impresión 3D rentable a personas y empresas de todo el mundo. Con una experiencia demostrada en el sector, un espíritu innovador y respaldada por el conglomerado empresarial electrónico líder del mundo, Kinpo Group, XYZrobot se fundó en 2015. El espíritu de innovación se plasmó en forma del robot Y-01 Bolide. El Bolide está diseñado para llevar soluciones robóticas que antes eran prohibitivas a un público más amplio con kits rentables. Este kit único de aprendizaje de ingeniería de bricolaje está previsto específicamente para mejorar la educación en ciencia, tecnología, ingeniería, arte y matemáticas de forma que se alcancen objetivos más interesantes y entretenidos. Con el Bolide, los usuarios pueden ajustar y configurar cada servomecanismo inteligente para crear posturas y secuencias variables. Los ajustes personalizados pueden guardarse mediante el programa XYZrobot Editor, disponible para sistemas Windows y Mac OS. XYZrobot Editor es compatible con el programa de código abierto Arduino (versión 1.0.6), lo que permite a los usuarios compartir un entorno de desarrollo de programación. Los usuarios pueden crear secuencias personalizadas de movimiento y compartirlas mediante la aplicación XYZrobot para dispositivos Android y Apple.	Gegründet im Jahr 2013, hat es sich XYZprinting zur Aufgabe gemacht, kostengünstigen 3D-Druck zu Privat- und Firmenkunden auf der ganzen Welt zu bringen. Mit bewährtem Expertenwissen, einem innovativen Geist und der Unterstützung durch die weltweit führende Herstellergruppe Kinpo Group, wurde XYZrobot im Jahr 2015 gegründet. Die Umsetzung des innovativen Geistes erfolgte in Form des Roboters Y-01 Bolide. Der Bolide wurde entwickelt, um einem breiteren Publikum bis dahin unerschwingliche Robotik-Lösungen durch kosteneffiziente Bausätze zu ermöglichen. Dieser einzigartige Lern-Baukasten ist speziell darauf ausgelegt, die STEAM Education zu erweitern, indem er fesselnde und unterhaltsame Herausforderungen bietet. Beim Bolide ist es dem Nutzer möglich, jeden Smart Servo anzupassen und zu konfigurieren, um so verschiedene Posen und Sequenzen zu erzeugen. Individualisierte Einstellungen können über die XYZrobot Editor Software, die für Windows und MacOS angeboten wird, gespeichert werden. Der XYZrobot Editor ist kompatibel mit der Arduino (v1.0.6) Open Source Software, was Benutzern ermöglicht, sich eine Programmierumgebung zu teilen. Die Benutzer können individuelle Bewegungssequenzen erstellen und sie über die XYZrobot App für Android und Apple Geräte teilen.
Action list	Lista de acciones	Liste der Aktionen
Action No.	Número de acción	Aktion Nr.
Add	añadir	hinzufügen
Add	Añadir postura	Pose hinzufügen
Alert	alerta	aufmerksam
Cancel	Cancelar	Abbrechen
Capture	Capturar	Erfassen
Close	Cerrar	Schließen
Close window	Cerrar ventana	Fenster schließen
Connection to {0}	Conexión a {0}	Verbindung zu {0}
Config	Configuración	Konfig
Confirm	confirmar	bestätigen
Connecting ...	Conectando…	Verbinden…
Connection timed out. Ensure power is turned on.	Tiempo de conexión excedido. Asegúrate de que está encendido.	Verbindungszeit überschritten. Überprüfen Sie, dass das Gerät eingeschaltet ist.
Control editor	Editor de control	Steuerungs-Editor
Create new project	Crear proyecto nuevo	Neues Projekt erstellen
Delay	retrasar	verzögern
Delete	borrar	löschen
Are you sure you want to delete?	¿Estás seguro de que deseas borrar?	Sind Sie sicher, dass Sie löschen möchten?
Delay	duración	dauer
Down	abajo	runter
Edit pose	Editar postura	Pose bearbeiten

Appendix
Español | Deutsche

ENGLISH	ESPAÑOL	DEUTSCHE
Edit sequence	Editar secuencia	Sequenz bearbeiten
Create failed. Duplicate name.	No se ha podido crear. Nombre duplicado.	Erstellen fehlgeschlagen. Namen duplizieren.
Import failed. Duplicate name.	No se ha podido importar. Nombre duplicado.	Import fehlgeschlagen. Namen duplizieren.
Can't open file.	No se puede abrir el fichero.	Öffnen der Datei nicht möglich.
Error	error	fehler
Exit	salida	ausgang
Can't export file	No se puede exportar el fichero.	Export der Datei nicht möglich.
Export to AVR	Exportar a AVR	Exportieren als AVR
Do you want to save changes before closing?	¿Quieres guardar los cambios antes de cerrar?	Möchten Sie vor dem Schließen die Änderungen speichern?
Halt	Parada	Halt
Help	Ayuda	Hilfe
Import	Importar	Import
L1	L1	L1
L2	L2	L2
L3	L3	L3
Left	izquierda	linkes
Left arm	Brazo izquierda	linkes Arm
Left back leg	Pata trasera izquierda	linkes hinterbein
Left front leg	Pata delantera izquierda	linkes vorderbein
Left leg	Pata izquierda	linkes Bein
Left middle leg	Pata central izquierda	linkes mittleres Bein
Live pose update	Actualización de postura en vivo	Live-Aktualisierung der Pose
Loading...	Cargando...	Laden…
Loop	Bucle	Loop
Maximize window	Maximizar ventana	Fenster maximieren
Minimize window	Minimizar ventana	Fenster minimieren
Model	modelo	Modell
Model does not match.	El modelo no coincide.	Modell passt nicht.
Editor v2.0	Editor v2.0	Editor v2.0
Move down	Mover hacia abajo	Runter bewegen
Move up	Mover hacia arriba	Hoch bewegen
(ms)	(ms)	(ms)
A file with the same name already exists in the folder. Current contents will be overwritten if file is replaced.	Ya existe un fichero con ese nombre en la carpeta. Los contenidos actuales se sobrescribirán si se sustituye el fichero.	In dem Ordner existiert bereits eine Datei des selben Namens. Die momentanen Inhalte werden überschrieben, wenn die Datei ersetzt wird.
already exists. Do you want to replace it?	Ya existe. ¿Quieres sustituirlo?	Existiert bereits. Ersetzen?
No default pose. Add a pose and define it as default.	No hay postura por defecto. Añade una postura y defínela como postura por defecto.	Keine Standard-Pose. Fügen Sie eine Pose hinzu und definieren Sie sie als Standard.
No default pose. Unable to complete command. Define a default pose.	No se ha podido completar la orden. Define una postura por defecto.	Ausführung des Befehls nicht möglich. Definieren Sie eine Standard-Pose.
There is an unspecified pose in the sequence {0}. Assign the pose in Sequence editor page before exporting AVR file.	Hay una postura no especificada en la secuencia {0}. Asigna la postura en la página de edición de secuencia antes de exportar el fichero AVR.	In der Sequenz {0} gibt es eine nicht spezifizierte Pose. Teilen Sie im Sequenz-Editor die Pose zu, bevor Sie dir AVR-Datei exportieren.
Export failed. AVR file too large.	No se ha podido exportar. El fichero AVR es demasiado grande.	Export fehlgeschlagen. AVR-Datei zu groß.

ENGLISH	ESPAÑOL	DEUTSCHE
Invalid naming. Name cannot start with D_ or E_ designation.	Nombre no válido. El nombre no puede comenzar por D_ ni E_.	Ungültiger Name. Der Name darf nicht mit D_ oder E_ beginnen.
Enter project name.	Introduce nombre del proyecto.	Projektnamen eingeben.
Music	música	Musik
Music path	Ruta de la música	Musik-Pfad
Name	nombre	name
Duplicate name exists	Existe un nombre duplicado	Duplikat-Name existiert bereits.
Sequence name cannot be the same as pose name.	El nombre de la secuencia no puede ser el mismo que el nombre de la postura.	Der Sequenz-Name darf nicht der selbe wie der Posen-Name sein.
Pose name cannot be the same as sequence name.	El nombre de la postura no puede ser el mismo que el nombre de la secuencia.	Der Posen-Name darf nicht der selbe wie der Sequenz-Name sein.
Does not meet naming convention requirement.	No cumple los requisitos de convención de nomenclatura.	Entspricht nicht den Anforderungen für Namen.
Cannot begin with a number or use special characters. Minimum of two characters.	No puede comenzar con un número ni utilizar caracteres especiales. Mínimo dos caracteres.	Darf nicht mit einer Nummer beginnen oder Sonderzeichen beinhalten. Mindestens zwei Zeichen.
New	Nuevos	Neue
New pose settings	Nuevos ajustes de postura	Neue Posen-Einstellungen
New sequence settings	Nuevos ajustes de secuencia	Neue Sequenz-Einstellungen
No	no	Nein
Not connected	No conectado	Nicht verbunden
Now editing pose: {0}	Editando postura: {0}	Editiere jetzt Pose: {0}
Now editing sequence: {0}	Editando secuencia: {0}	Editiere jetzt Sequenz: {0}
Now selecting sequence: {0}	Seleccionando secuencia: {0}	Wähle jetzt Sequenz: {0}
Ok	Confirmar	Bestätigen
Open	Abrir	Öffnen
Parameters	Parámetro	Parameter
First, create a new robot.	Primero crea un nuevo robot.	Erstellen Sie zuerst einen neuen Roboter.
First, create a pose name.	Primero crea un nombre de postura.	Erstellen Sie zuerst einen neuen Posen-Namen.
First, create a sequence name.	Primero crea un nombre de secuencia.	Erstellen Sie zuerst einen neuen Sequenz-Namen.
Create or select a sequence to edit.	Crear o seleccionar una secuencia para editarla.	Sequenz zum Bearbeiten erstellen oder auswählen.
Select a pose to edit.	Seleccionar una postura para editarla.	Pose zum Bearbeiten erstellen.
Select a sequence to edit.	Seleccionar una secuencia para editarla.	Pose zum Bearbeiten auswählen.
Port	puerto	Port
Port (Ex. COM1, dev, ttyUSB0)	puerto (Ej.: COM1, dev, ttyUSB0)	Port (Ex. COM1, dev, ttyUSB0)
Port setting	Ajustes de puerto	Port einstellen
Pose	postura	Posen
Pose editor	Editor de postura	Posen-Editor
Pose list	Lista de posturas	Liste der Posen
Pose name	Nombre de postura	Posen-Name
Project	Proyecto	Projekt
Project:{0} unmatched condition	Proyecto: {0} estado sin igual	Projekt: {0} Bedingungen stimmen nicht überein
Project name	Nombre de proyecto	Projekt-Name
R1	R1	R1
R2	R2	R2
R3	R3	R3

Appendix
Español | Deutsche

ENGLISH	ESPAÑOL	DEUTSCHE
Relax	relajar	entspannen
Remote control setting	Ajustes de control a distancia	Fernbedienungs-Einstellungen
Remove	Eliminar	Entfernen
Rename	Renombrar	umbenennen
Rename pose	Renombrar postura	Pose umbenennen
Rename sequence	Renombrar secuencia	Sequenz umbenennen
Right	derecha	rechte
Right arm	Brazo derecho	rechter Arm
Right back leg	Pata trasera derecha	rechte hinterbein
Right front leg	Pata delantera derecha	rechte vorderbein
Right leg	Pata derecha	rechte Bein
Right middle leg	Pata central derecha	rechte mittleres Bein
XYZrobot	XYZrobot	XYZroboter
Button 1	Botón 1	Button 1
Button 2	Botón 2	Button 2
Button 3	Botón 3	Button 3
Button 4	Botón 4	Button 4
Robot button setting	Ajustes de botón de robot	Roboter-Button-Einstellungen
Run	Reproducir	Ausführen
Sample player	Reproductor de ejemplo	Beispiele abspielen
Sample pose	Postura de ejemplo	Beispiel-Pose
Sample sequence	Secuencia de ejemplo	Beispiel-Sequenz
Save	Guardar	Speichern
Save As	Guardar como	speichern unter
Save complete	Guardado completado	Speichern vollständig
Search	búsqueda	suchen
Select communications port	Seleccionar puerto de comunicaciones	Kommunikations-Port auswählen
Sequence editor	Editor de secuencia	Sequenz-Editor
Sequence list	Lista de secuencias	Liste der Sequenzen
Sequence name	Nombre de secuencia	Sequenz-Name
Serial port initialization start...	Comienza la inicialización del puerto serie...	Serienanschluss-Initialisierung starten…
Serial number	Número de serie	Seriennummer
# of servos	Número de servos	# der Servos
Set	Establecer	Einstellen
XYZrobot Editor V1.0	XYZrobot Editor	XYZRoboter Editor
Tool	Instrumentos	Werkzeuge
Transitions	Registros	Aufzeichnungen
Up	arriba	oben
Warning	¡Advertencia	Warnung
Yes	si	ja

CLOSE ◁——▷ OPEN