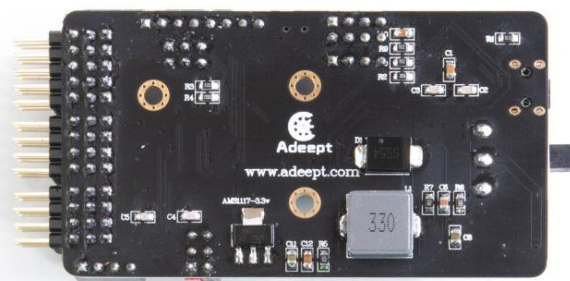
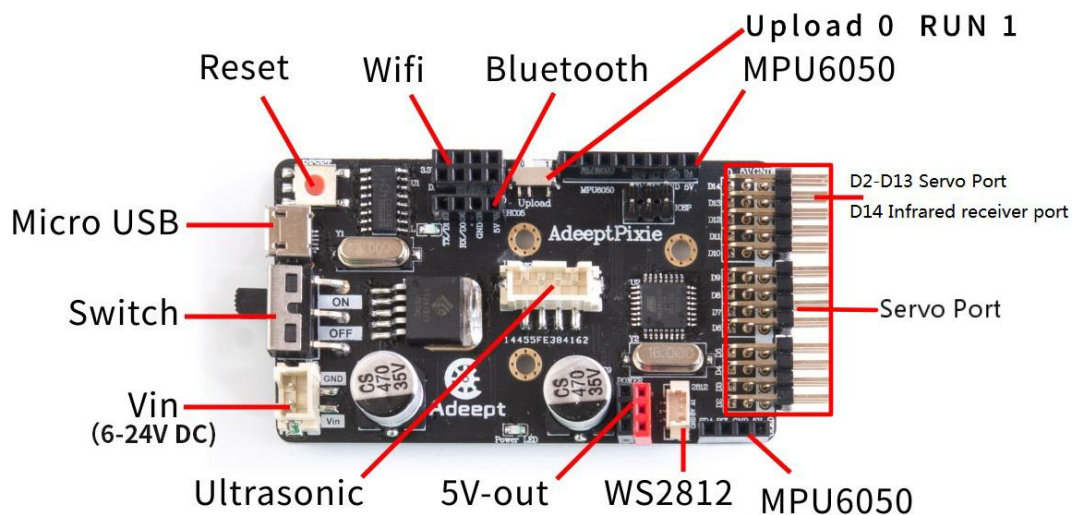


## Lesson 2 About the AdeptPixie Driver Board

When you get the hexapod spider robot, you will see a board with its name printed on it called: AdeptPixie. It is an important part of the hexapod spider robot. There are many interfaces on the AdeptPixie driver board. With these interfaces, you can connect some sensors and electronic hardware modules, so that you can achieve many extended functions. Our hexapod spider robot product needs to be used with Arduino IDE, let's first learn about the AdeptPixie driver board.



【Vin】 : it is an interface for external power supply, range: 6-24V.

【Switch】 : it is the switch of the drive board, ON is to open, and OFF is to close.

【 Micro USB 】 : The Micro USB interface can connect the driver board to a

computer or other equipment, and can also supply power to the driver board.

**【WS2812】** :it is the pin interface of WS2812 Module.

**【5V-out】** :Output 5V interface.

**【MPU6050】** :it is the interface of MPU6050 sensor.

**【Servo Port】** :it is the interface of Servo, each row corresponds to a Servo.

**【Ultrasonic】** :it is the interface of Ultrasonic.

**【Reset】** : restarting the driver board.

**【Bluetooth】** : it is the pin interface of Bluetooth. Bluetooth is an open global specification for wireless data and voice communication. It is a special short-range wireless technology connection based on a low-cost short-range wireless connection to establish a communication environment for fixed and mobile devices.

**【Wifi】** : the interface of ESP8266 module.

**【Upload 0 RUN 1】** : There are two numbers 0 and 1 on this switch. If you have connected the ESP8266 module to the [Wifi] port, you need to turn the switch to 0 when uploading the program. If you have not connected the ESP8266 module to the **【Wifi】** port, you do not need to turn the switch when uploading the program, and it can be in either 0 or 1 state. When you upload the program successfully, you must turn the switch to the 1 position. As shown below:

