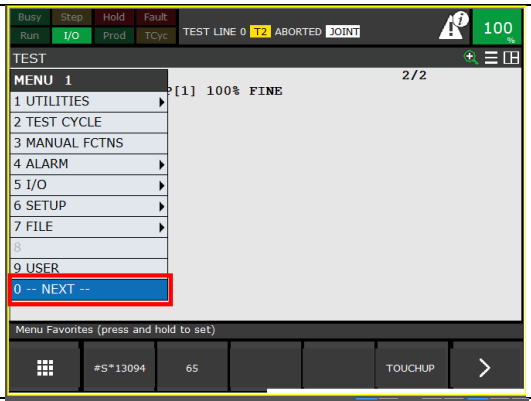
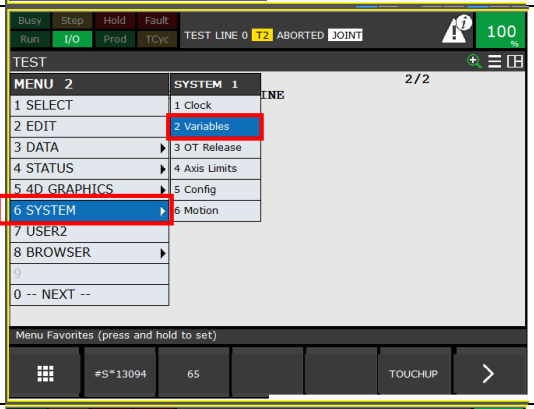
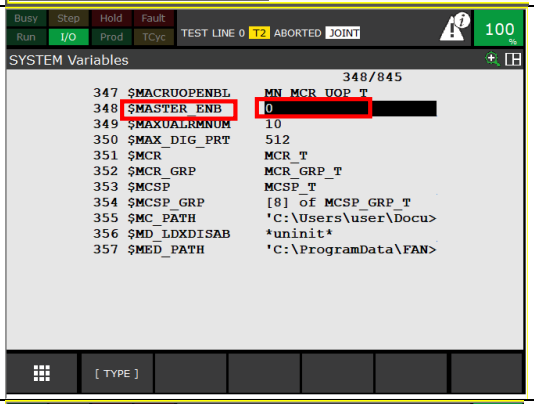
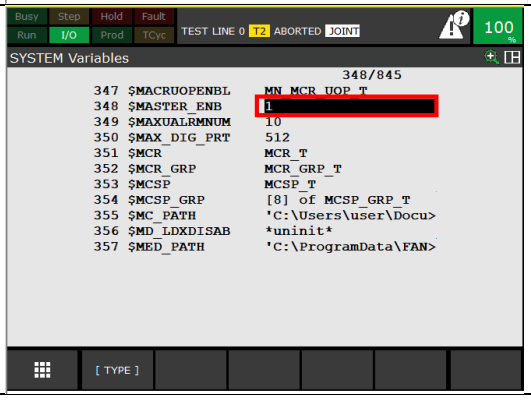
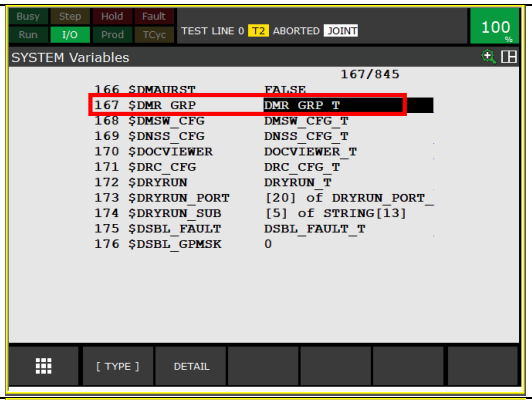
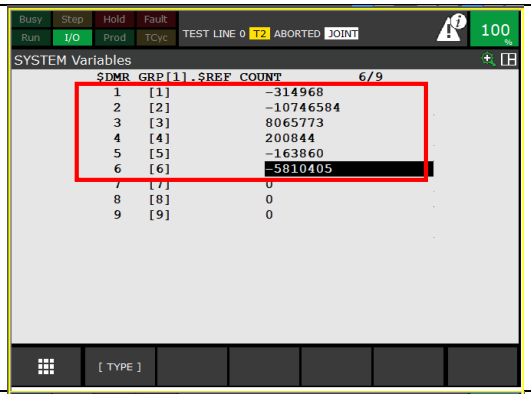
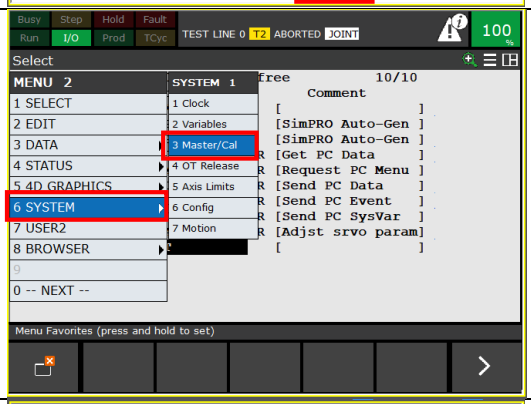
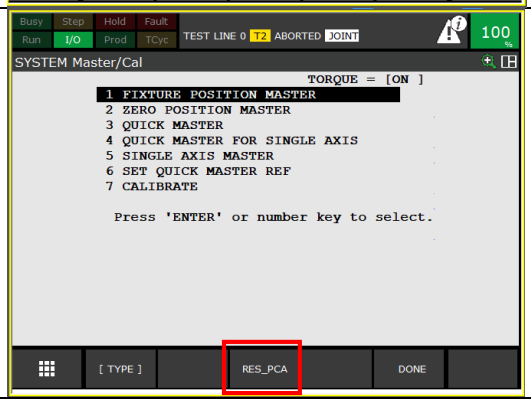
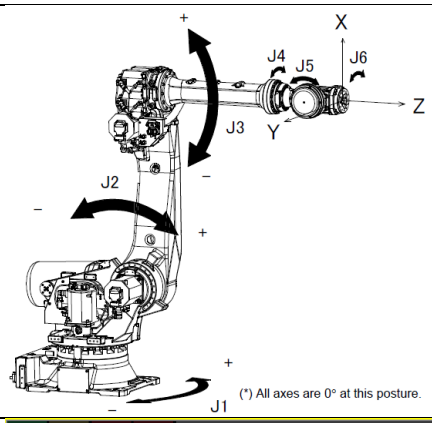
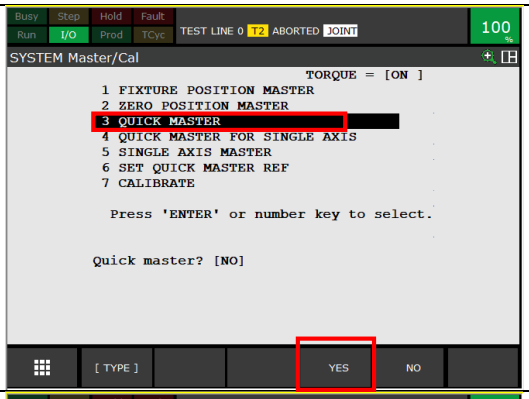
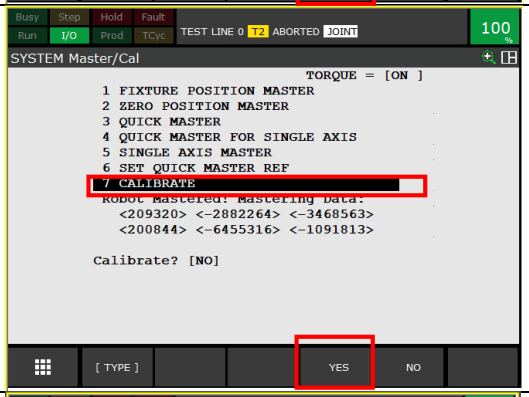
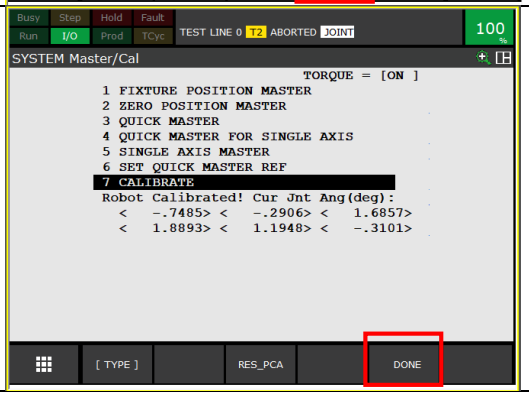
Quick Mastering

1. System Variables 수정/입력

(1)			[Menu] 누르기 -> '---NEXT---' 선택
(2)			'SYSTEM' 선택 -> 'Variables' 선택
(3)			'MASTER_ENB' 찾기 (기종별로 변수의 수가 다르므로, 변수 번호는 다를 수 있음.)
(4)			'MASTER_ENB' 선택 -> '1' 입력 (조작 전부터 이미 1로 설정되어 있을 수 있음.)

(5)			'DMR_GRP' 선택 -> [ENTER] 누르기
(6)			[ENTER] 누르기
(7)			Robot Data sheet의 'Master_Count' 확보. (Robot별로 값이 틀림. 해당 로봇의 값을 넣어야 함.)
(8)			'REF_COUNT' 선택 -> [ENTER]

(9)			(7) Data Sheet에서 확보한 Master_count 값을 입력
(10)			Master_count값 입력후, 'REF_DONE'을 'FALSE' -> 'TRUE' 변경 (Quick Mastering은 Ref_count값을 기준으로 mastering을 실행함으로, 사전에 입력이 되어있어야 함)
(11)			[MENU] 누르기 -> 'SYSTEM' 선택 -> 'Master/Cal' 선택 ('Master/Cal' 항목은 (2)에서는 보이지 않았음. (4)에서 system variable를 바꾸었기 때문)
(12)			'Pulse mismatch' 등의 알람이 뜰 경우, 'RES_PCA' 를 선택하여 알람을 임시로 해제함.

(13)		-모든 축을 15도 이상씩 회전. -'아이 마크(스티커)'를 참고하여, 각 축을 0도로 맞춤. (0도 맞추기 위해 불필요한 경우에도 모든 축을 15도 이상씩 회전시켜야 함)
(14)		0도 맞추기 완료 -> 'Quick Maaster' 선택 -> [YES]
(15)		'Calibrate' 선택 -> [YES]
(16)		Calibrate 완료 후, 로봇 정상작동 확인되면, 'DONE' 선택 -> 끝.