

Deactivate the Fall Manager

The fall manager is designed to protect NAO when it falls. This is useful in all cases but it might bother you when Nao climbs in the trolley.

How does it work?

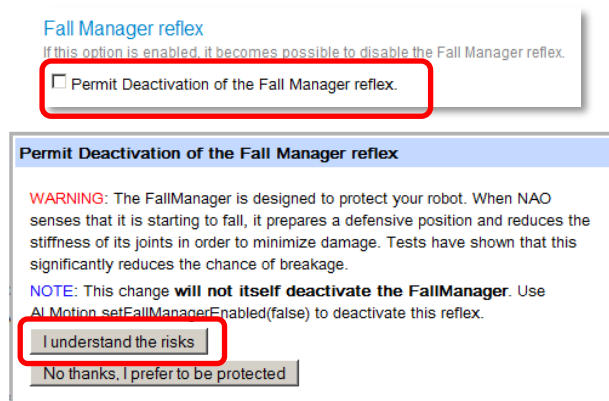
The detailed explanation can be found [in the documentation](#).

Why deactivating the Fall Manager?

To climb a stair, you need to balance the robot on one foot to be able to move the second foot to the upper level, and then transfer the weight to the lower foot to the upper foot. During the transfer, the center of mass of the robot will move from one foot to the other while they are not at the same level, so the robot may feel that it is falling and trigger its protection.

How to deactivate it?

1. You need to allow the deactivation, on the “former NAO web page” in the “Settings”. See [the documentation](#).



Fall Manager reflex
If this option is enabled, it becomes possible to disable the Fall Manager reflex.

☐ Permit Deactivation of the Fall Manager reflex.

Permit Deactivation of the Fall Manager reflex

WARNING: The FallManager is designed to protect your robot. When NAO senses that it is starting to fall, it prepares a defensive position and reduces the stiffness of its joints in order to minimize damage. Tests have shown that this significantly reduces the chance of breakage.

NOTE: This change **will not itself deactivate the FallManager**. Use `Al Motion setFallManagerEnabled(false)` to deactivate this reflex.

2. Then, you can deactivate the reflex with the Choregraphe box “Set Fall Manager” or with the python function [motion.setFallManagerEnabled\(False\)](#)

