

Lesson 2 Smart Phone Control

1. APP Installation

Android user: Please transfer the installed pack to your smart phone to install.

iOS user: Please search “Wonderbot” in App Store.

2. Device Connection



Note:

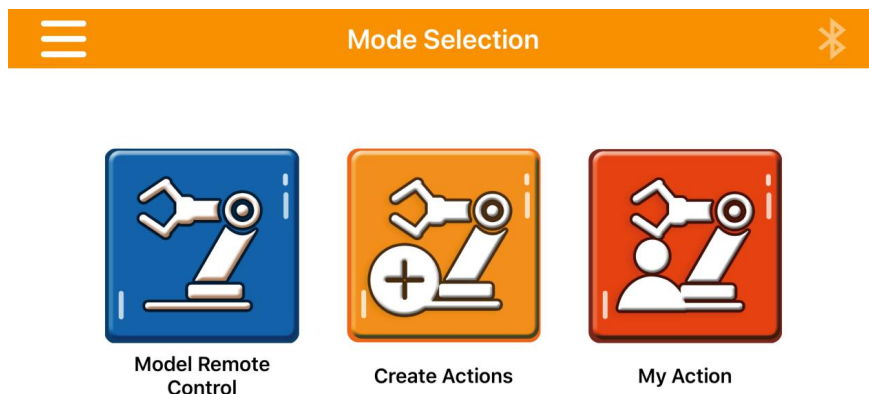
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- 1) Please turn on the Bluetooth and GPS service before opening the APP.
 - 2) Please use the Bluetooth button in the APP to pair and connect with the device.

Do not pair with the key in the phone settings.

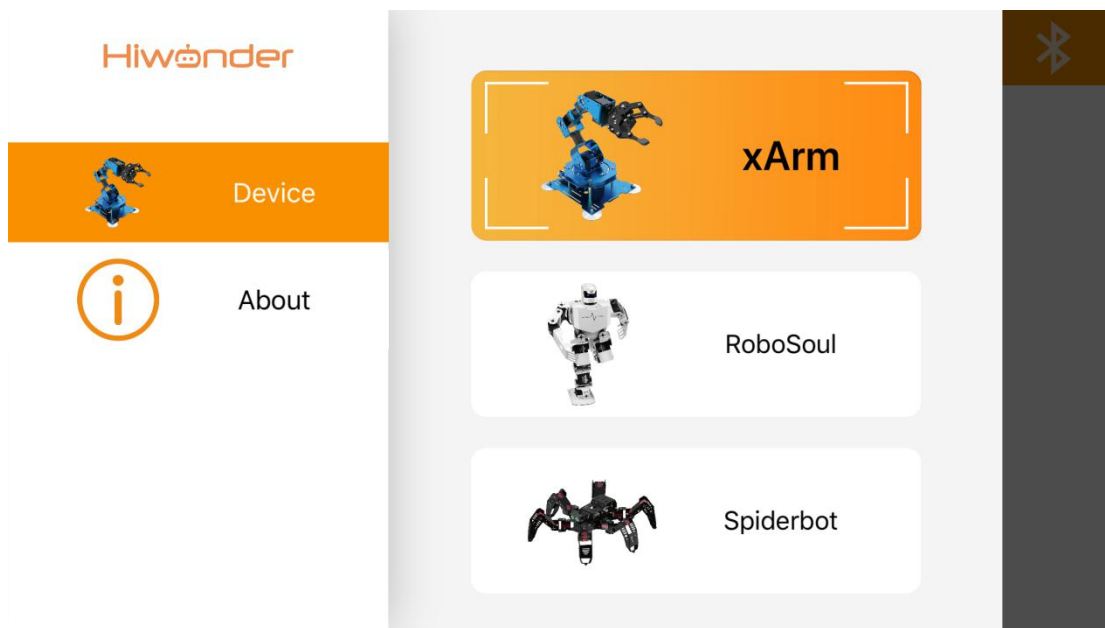
3) This lesson takes the iOS version APP as an example. The system version requirements: Android 7.0 or above, iOS 9.0 or above.

Step 1: Turn on the robotic arm.

Step 2: Open the Wonderbot APP to the interface as below.



If your interface is different, please click  icon and “Settings” to choose the “xArm”.

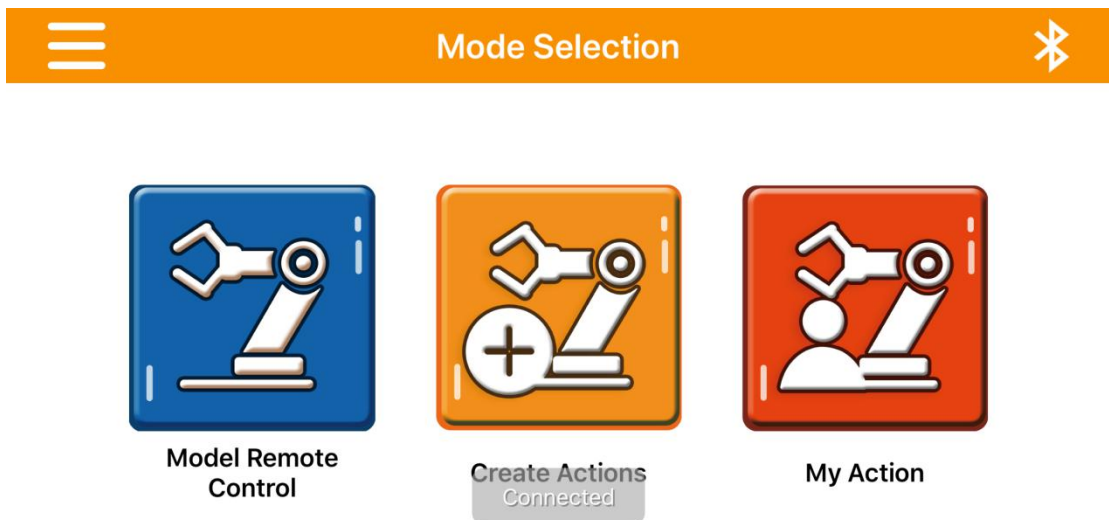


Step 3: Click the flashing Bluetooth icon on the interface to search the device.
Please select the “xArm” later.





Step 4: Wait for a while, the Bluetooth icon will stop flashing and stay on. The "Bluetooth is connected" will prompt appear.



3. Mode Instruction

Mode 1 Model Remote Control: Combine the two-dimensional screen with the button to control the movement of the robotic arm easily.

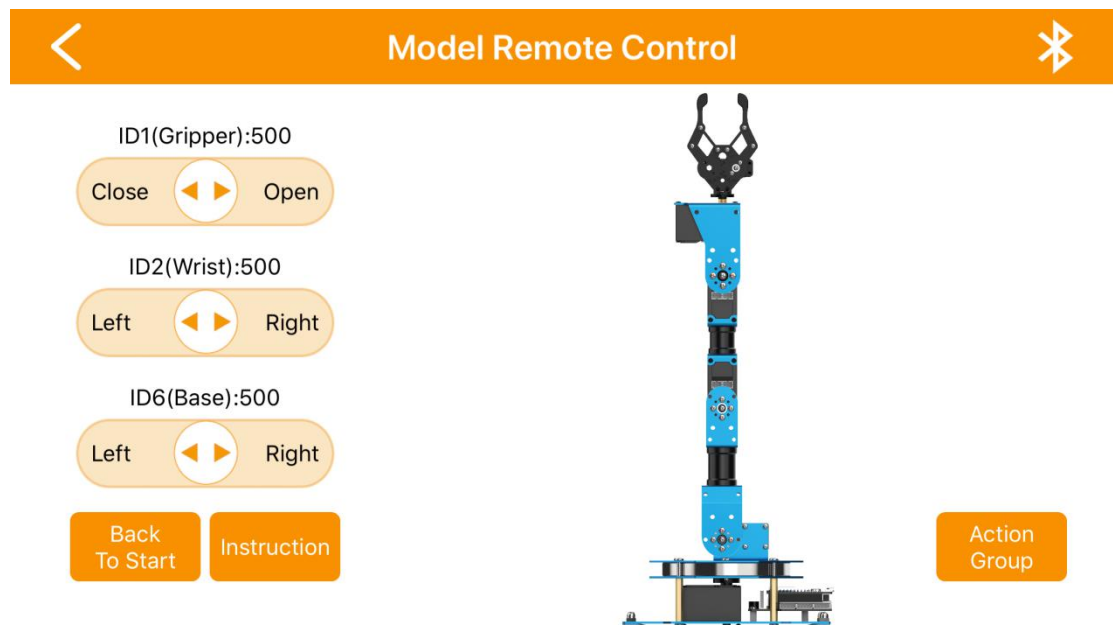
Mode 2 Create Actions: Under this mode, you can program actions, debug and record the data of robotic arm.

Mode 3 My Action: You can store, display and delete the custom actions.

For the detailed instruction of programming in APP, please go to the folder “Expansion Lesson/Smart Phone APP Programming”.

4. Button Instruction

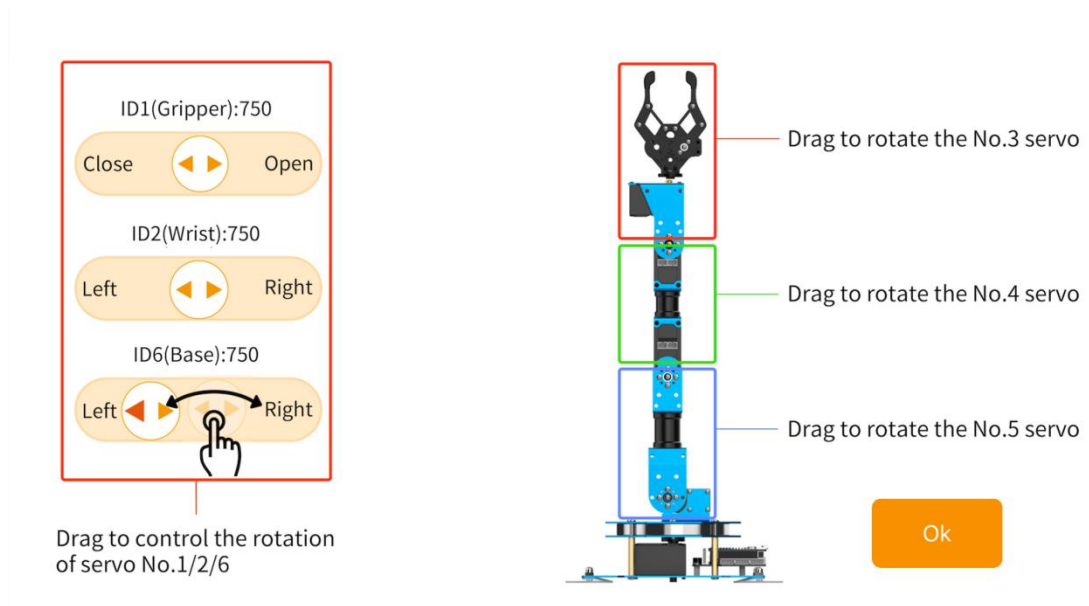
1) Under Mode 1 Model Remote Control, the interface is as below:



2) On the right side, there is a 2D animation of xArm 1S. You can drag to control the movement but also the check the stance after rotation. Buttons on the left side support to control the rotation of gripper, wrist and bottom.

3) Click “Action Group” to execute the action groups which are downloaded into the robotic arm already. For more details, please go to folder “3. xArm 1S PC Software and APP Learning/Lesson 3 APP Custom Control”.

4) Click “Operation Instruction” for operated method.



5) Click “Back to Start” to call all the servos back to middle position.

