

## ROBOSAPIEN SECRET #2: CONDITIONAL REFLEX PROGRAMMING



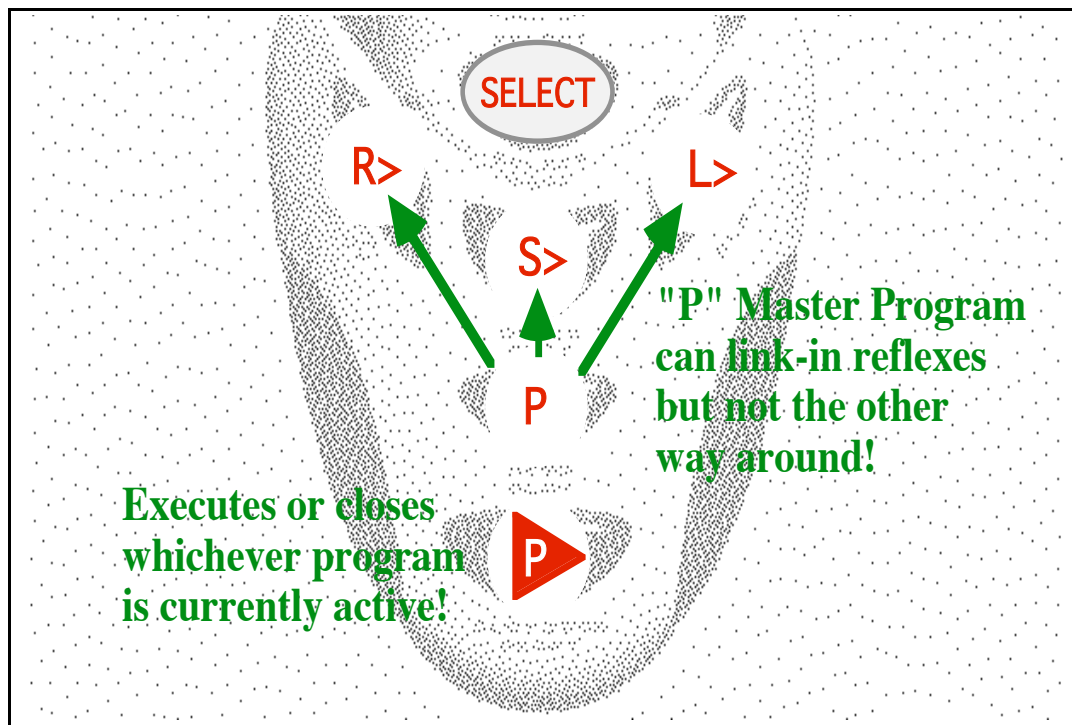
“Hey man, wanna... pull my finger?”

During master program **P>** playback, the robot can be set to "wait" for specific sensor inputs before advancing to the next program instruction. This works for all reflex sensors. When in Program Mode ("Beep, beep, beep"), you can press any of the reflex buttons (**R>**, **S>**, or **L>**), and that sensor will then be entered as a single "step" in the master program.

The master program can link in the reflexes, but not the other way around. If you try, the robot will give you an "Eeh!" noise, telling you that you've tried an illegal programming function.

When a touch reflex is in "conditional mode" during program playback, the robot ignores all other signals except a touch on that specific sensor (or a **STOP** command from the remote).

- The master program **P** is only 14 steps long, but can conditionally link in the Reflex sensors, each of which are 6 steps each for a total of 84. Each of the reflex sensors will behave just as they do normally, but only when it is their turn in the program.



During program playback, the robot can be set to “conditionally” wait for specific sensor inputs before advancing to the next instruction. This works for all reflex sensors, both sound and touch.

**PULL MY FINGER:**

A “touch” example is the “Pull My finger” conditional program below. After the robots power-on wakeup has finished, enter this...

Press R>  
 Select – Select – OOPS  
 Select - STOP  
 Press P>

STOP

Press L>  
 Select – Select – BURP  
 Select – STOP

Press P>

STOP

Press P  
 Select - STOP

**Left Forearm IN**  
**Right Forearm OUT**  
**Right Shoulder UP**  
**Right Forearm IN**  
**Right Forearm OUT**  
**R>**  
**Right Forearm IN**  
**Left Forearm OUT**  
**Left Shoulder UP**  
**Left Forearm IN**  
**Left Forearm OUT**  
**L>**  
**Select – Select – HIGHFIVE**

After entering the command, the robot will automatically execute your comedy routine. Press **STOP** to end, or **P>** to see again.

This routine will wait for someone to touch it, then the robot will offer his right hand. When the victim touches the sensor finger, the robot will pull his hand away, "retort" appropriately, then reset for the left side to await another victim.