Fig.1

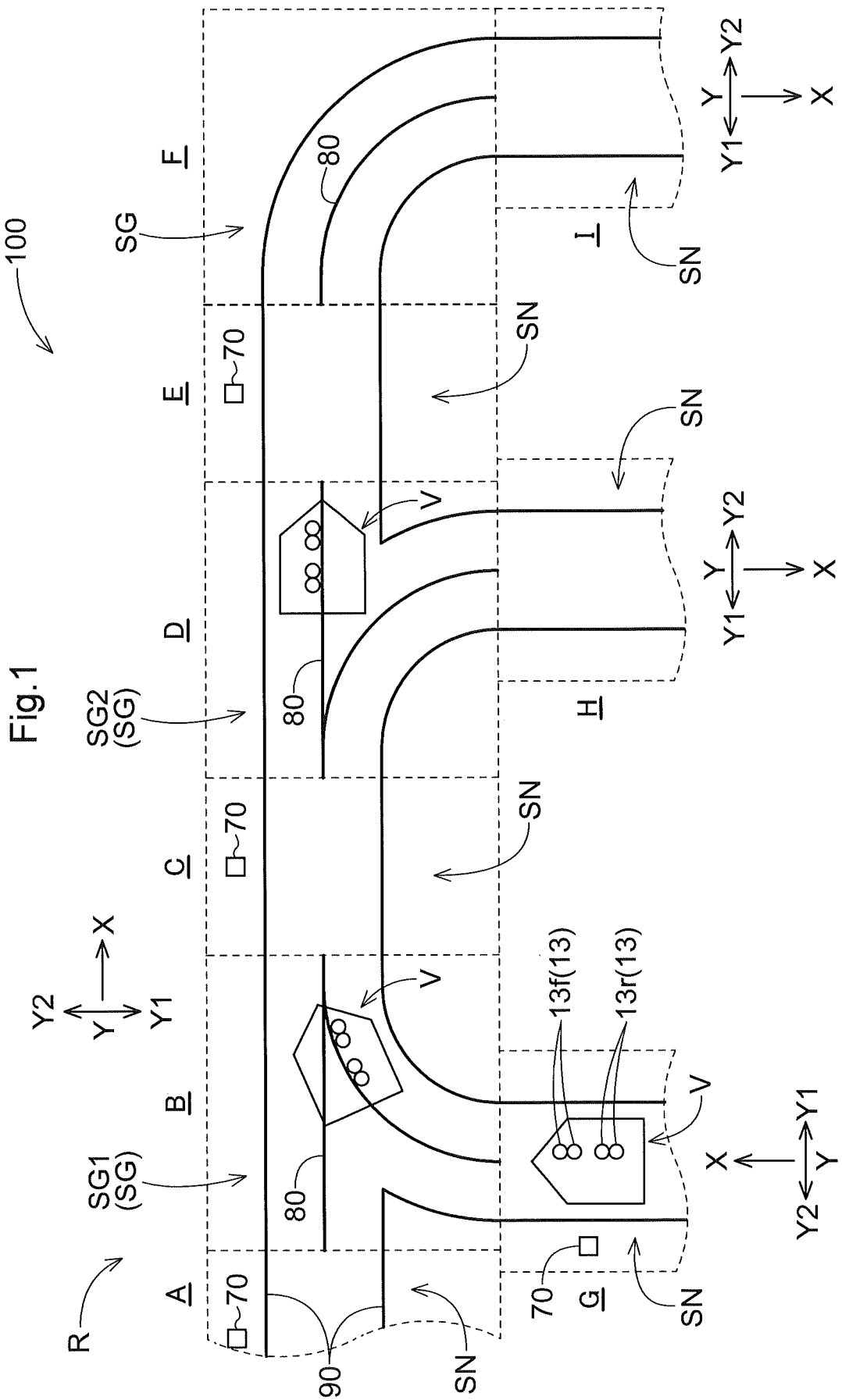

100
R
SG1 (SG)
SG2 (SG)
SG
A
B
C
D
E
F
G
H
I
70
80
90
SN
V
13f(13)
13r(13)
X
Y
Y1
Y2

Fig.2

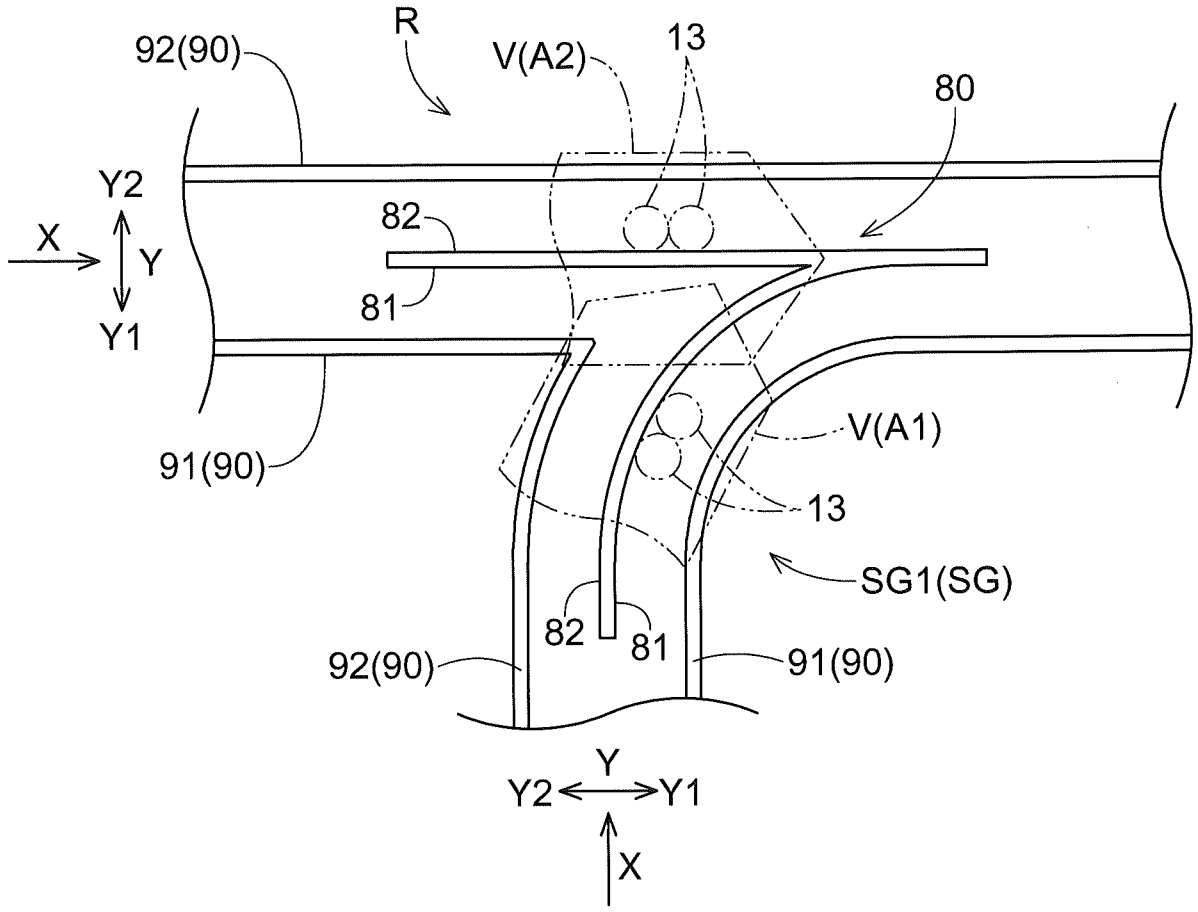

R
92(90)
V(A2)
13
80
Y2
X
Y
Y1
82
81
91(90)
V(A1)
13
SG1(SG)
82
81
92(90)
91(90)
Y
Y2
Y1
X

Fig.3

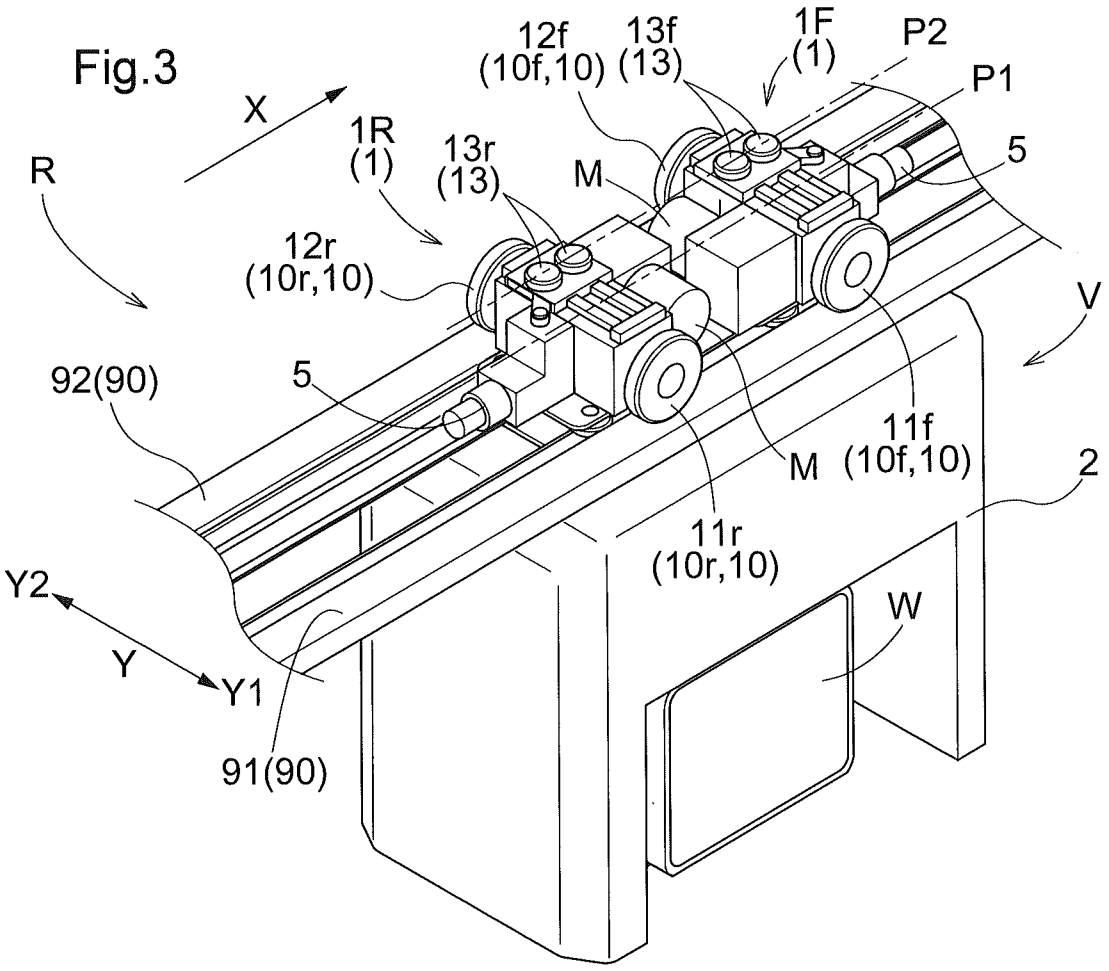

X
R
1R
(1)
13r
(13)
M
12f
(10f,10)
13f
(13)
1F
(1)
P2
P1
5
12r
(10r,10)
V
92(90)
5
M
11f
(10f,10)
2
11r
(10r,10)
W
Y2
Y
Y1
91(90)

Fig.4

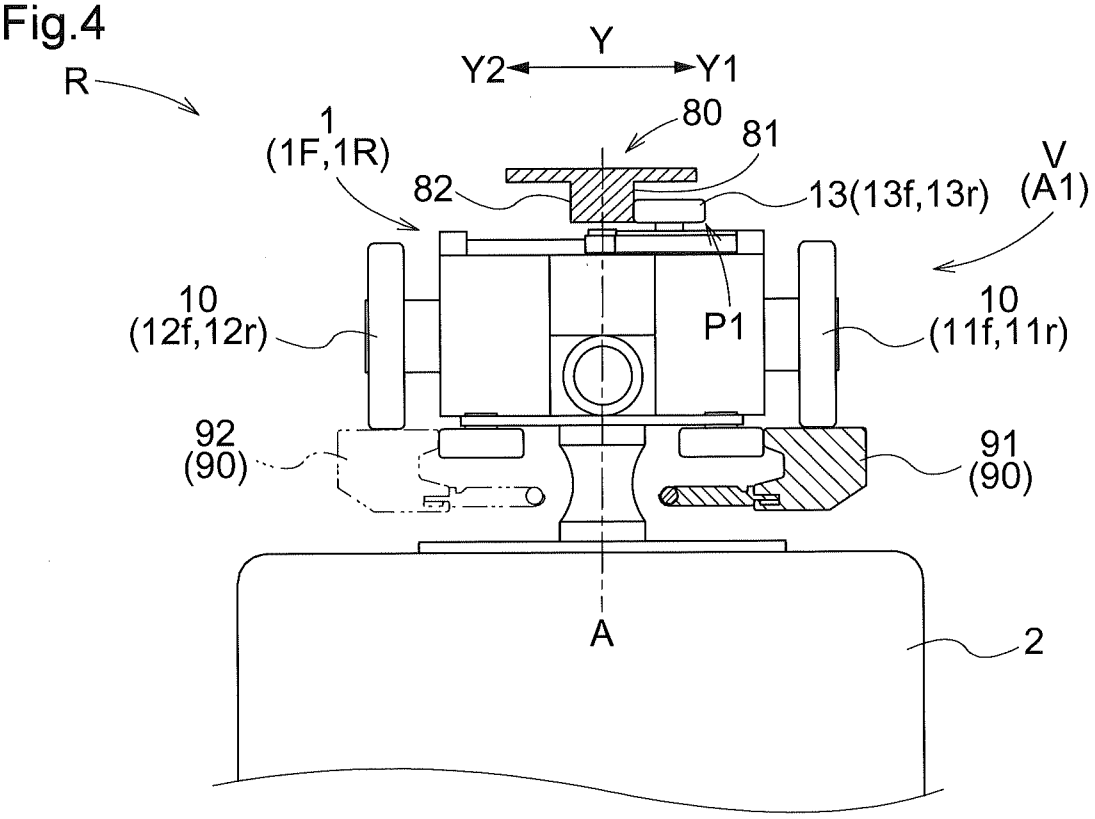

R
Y
Y2
Y1
1
(1F,1R)
80
81
82
13(13f,13r)
V
(A1)
10
(12f,12r)
P1
10
(11f,11r)
92
(90)
91
(90)
A
2

Fig.5

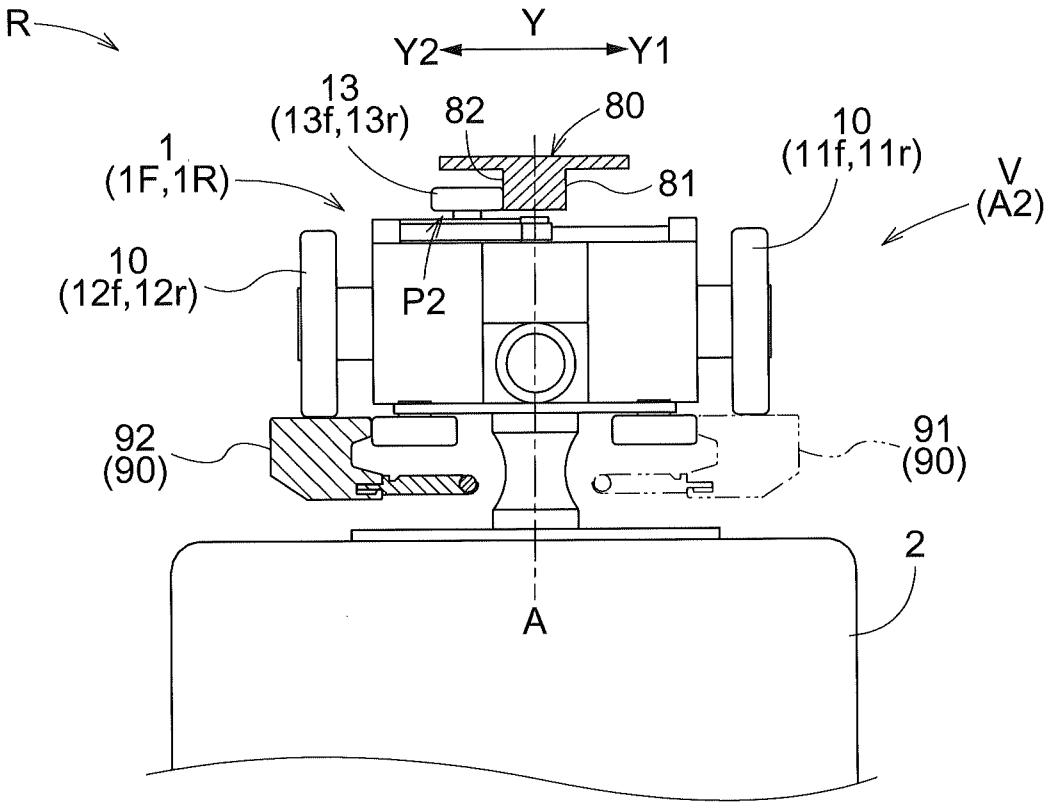

R
Y
Y2
Y1
13
(13f,13r)
82
80
10
(11f,11r)
1
(1F,1R)
81
V
(A2)
10
(12f,12r)
P2
92
(90)
91
(90)
2
A

Fig.6

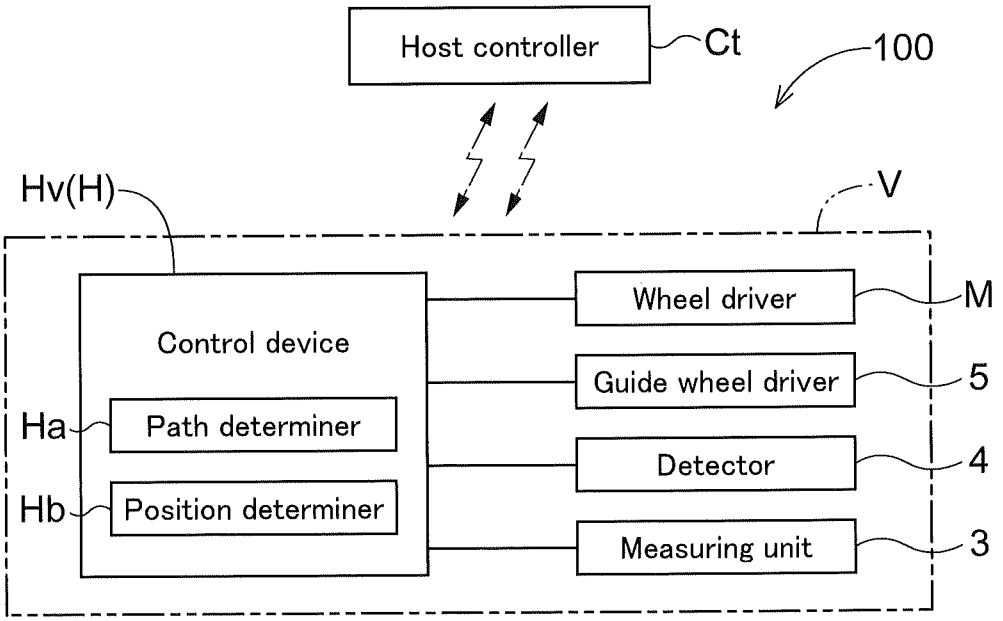

Host controller
Ct
100
Hv(H)
V
Control device
Ha
Path determiner
Hb
Position determiner
Wheel driver
M
Guide wheel driver
5
Detector
4
Measuring unit
3

Fig.7

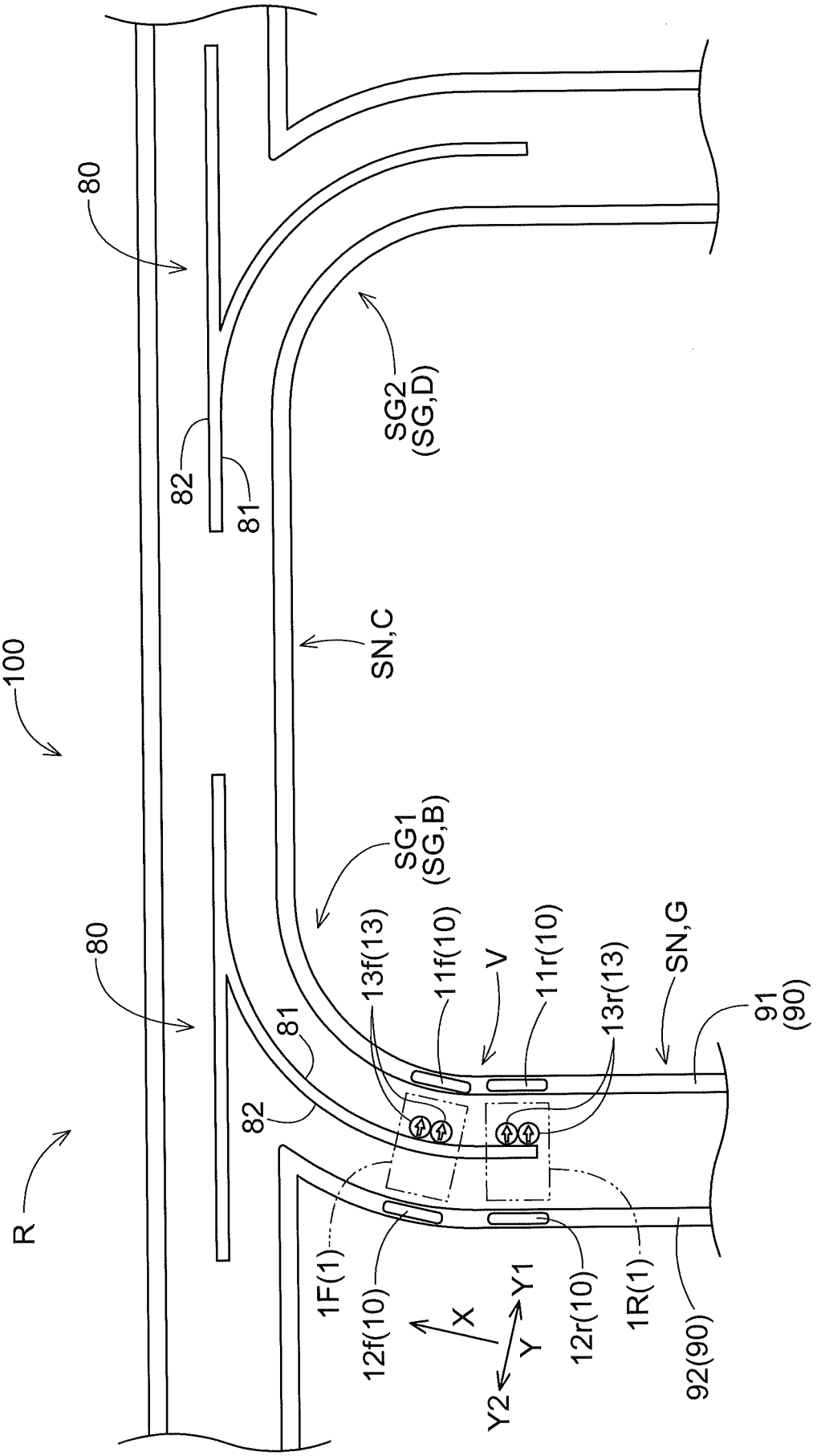

100
80
80
82
81
82
81
SG2
(SG,D)
SN,C
SG1
(SG,B)
13f(13)
11f(10)
V
11r(10)
13r(13)
SN,G
91
(90)
R
1F(1)
12f(10)
X
Y1
Y
Y2
12r(10)
1R(1)
92(90)

Fig.8

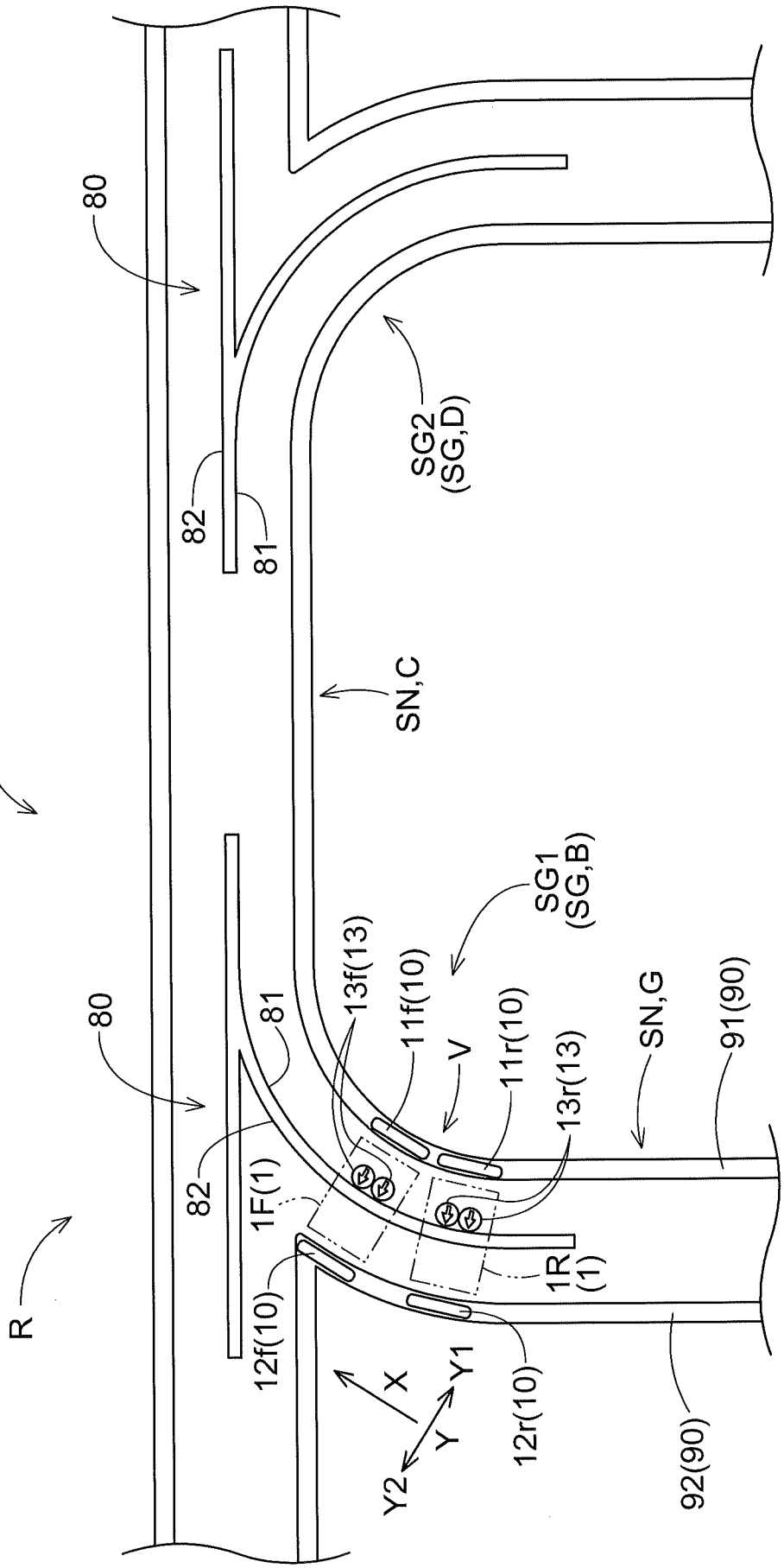

100
80
80
80
82
81
82
81
SG2
(SG,D)
SN,C
SG1
(SG,B)
13f(13)
11f(10)
V
11r(10)
13r(13)
SN,G
91(90)
1F(1)
1R
(1)
12f(10)
12r(10)
92(90)
R
X
Y1
Y
Y2

Fig.9

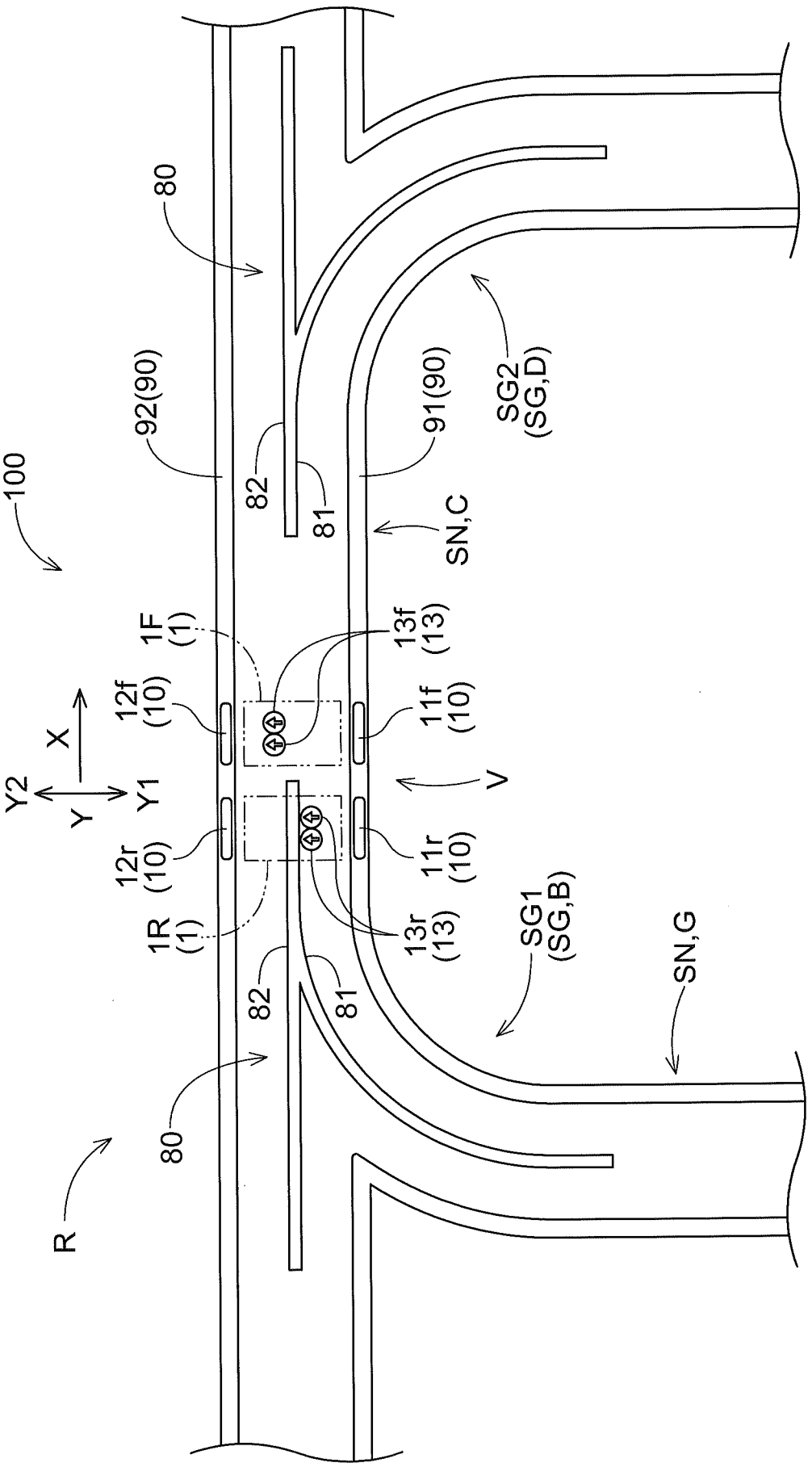

100
80
92(90)
91(90)
SG2
(SG,D)
82
81
SN,C
1F
(1)
13f
(13)
12f
(10)
11f
(10)
X
Y2
Y
Y1
V
12r
(10)
11r
(10)
1R
(1)
13r
(13)
SG1
(SG,B)
SN,G
82
81
80
R

Fig.10

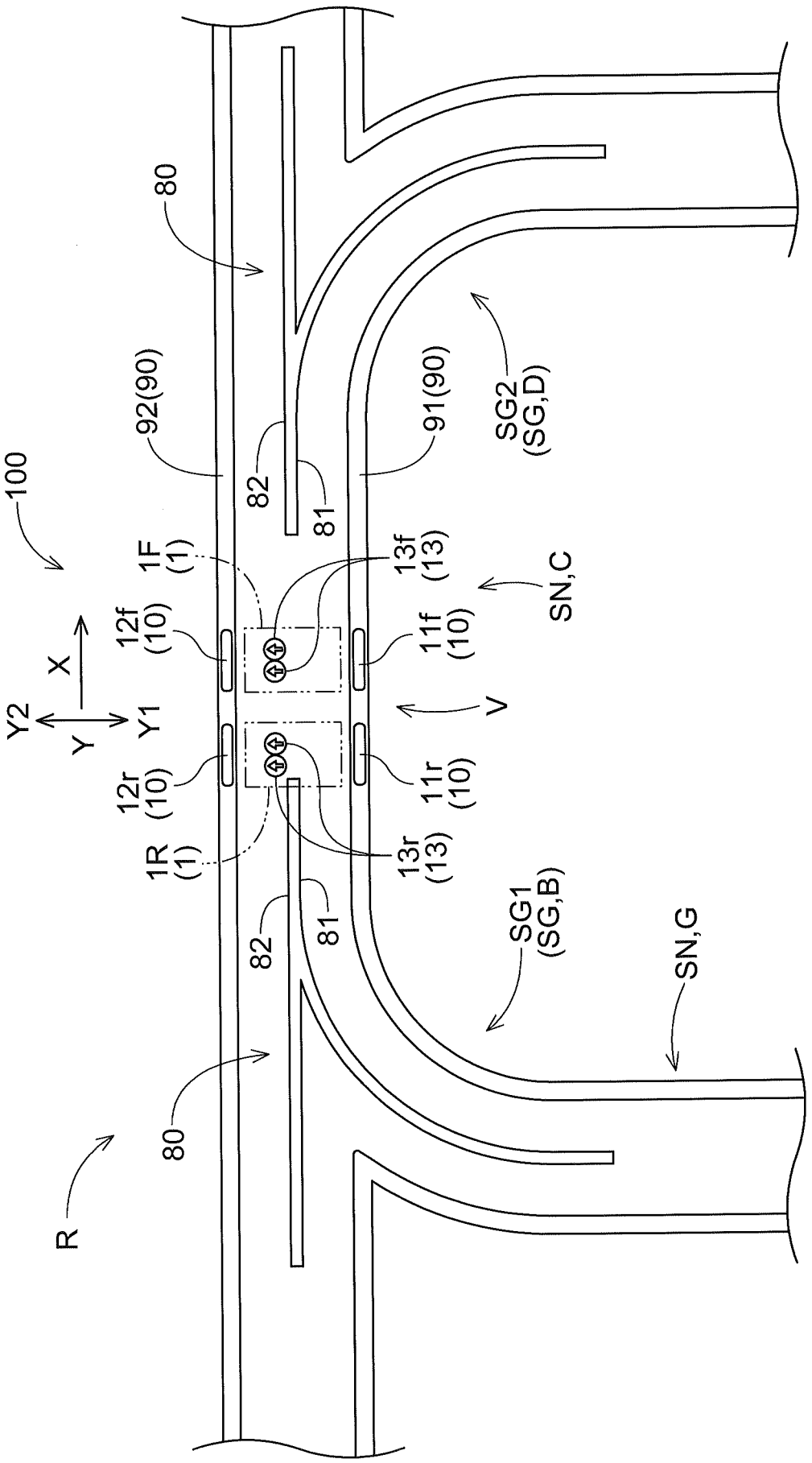

100
80
92(90)
91(90)
SG2
(SG,D)
82
81
1F
(1)
13f
(13)
12f
(10)
11f
(10)
SN,C
X
Y2
Y1
Y
V
12r
(10)
11r
(10)
1R
(1)
13r
(13)
SG1
(SG,B)
SN,G
R

Fig.11

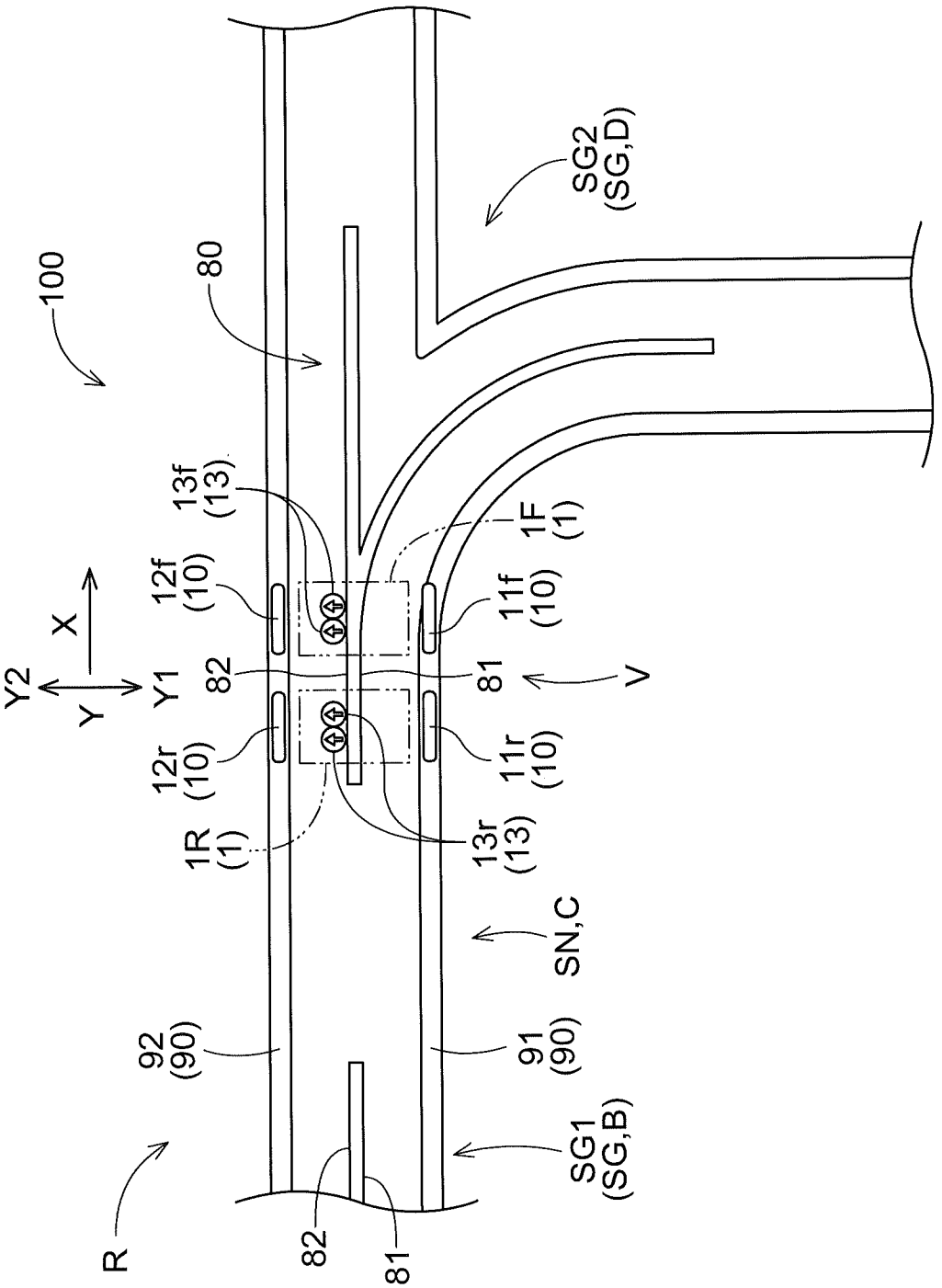

100
80
SG2
(SG,D)
13f
(13)
1F
(1)
12f
(10)
11f
(10)
X
Y2
Y
Y1
82
81
V
12r
(10)
11r
(10)
1R
(1)
13r
(13)
SN,C
92
(90)
91
(90)
SG1
(SG,B)
R
82
81

Fig.12

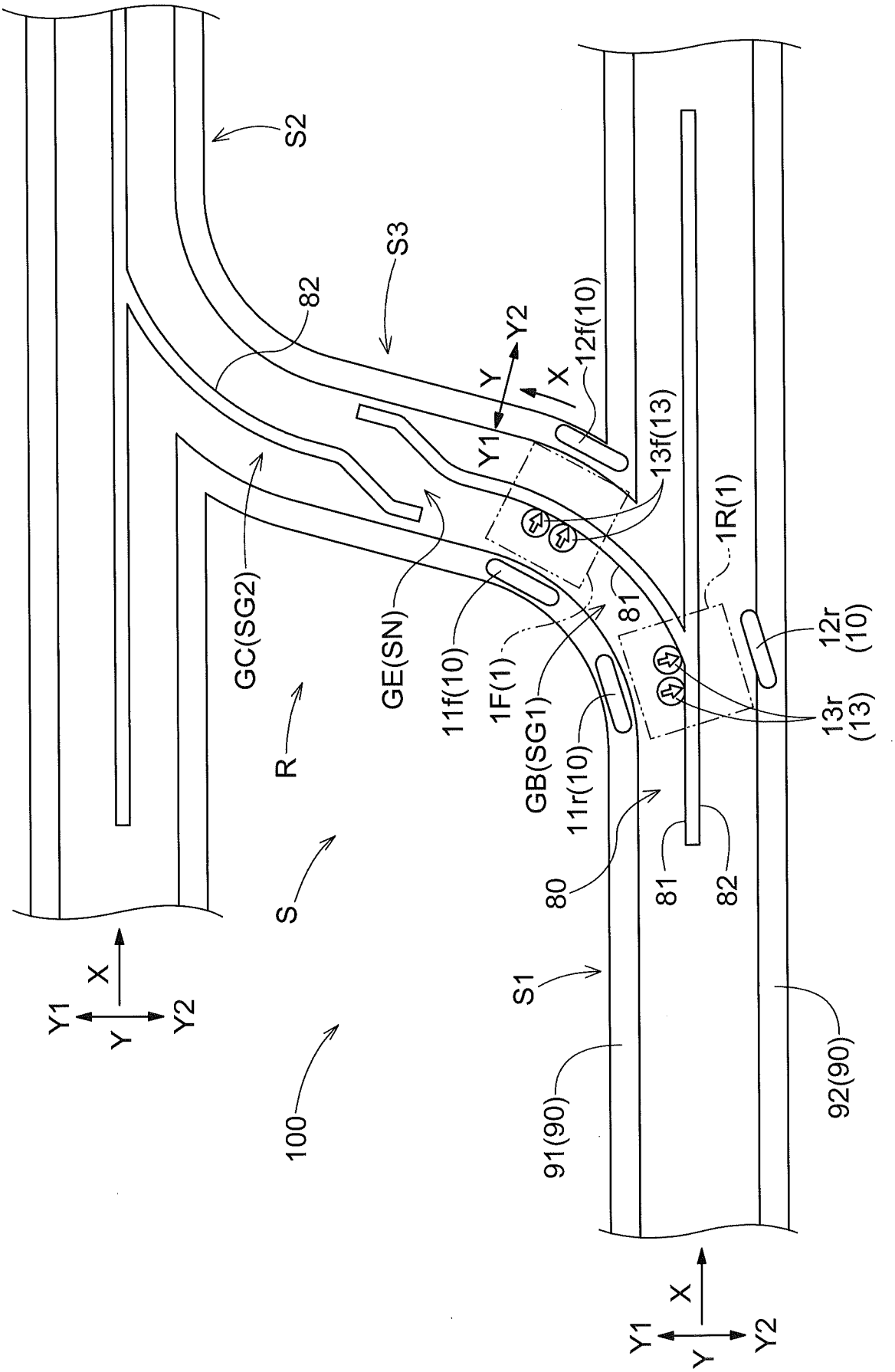

S2
S3
82
Y
Y2
X
Y1
12f(10)
13f(13)
1R(1)
GC(SG2)
GE(SN)
11f(10)
1F(1)
GB(SG1)
11r(10)
81
12r
(10)
13r
(13)
R
S
80
81
82
S1
91(90)
92(90)
100
Y1
X
Y
Y2

Fig.13

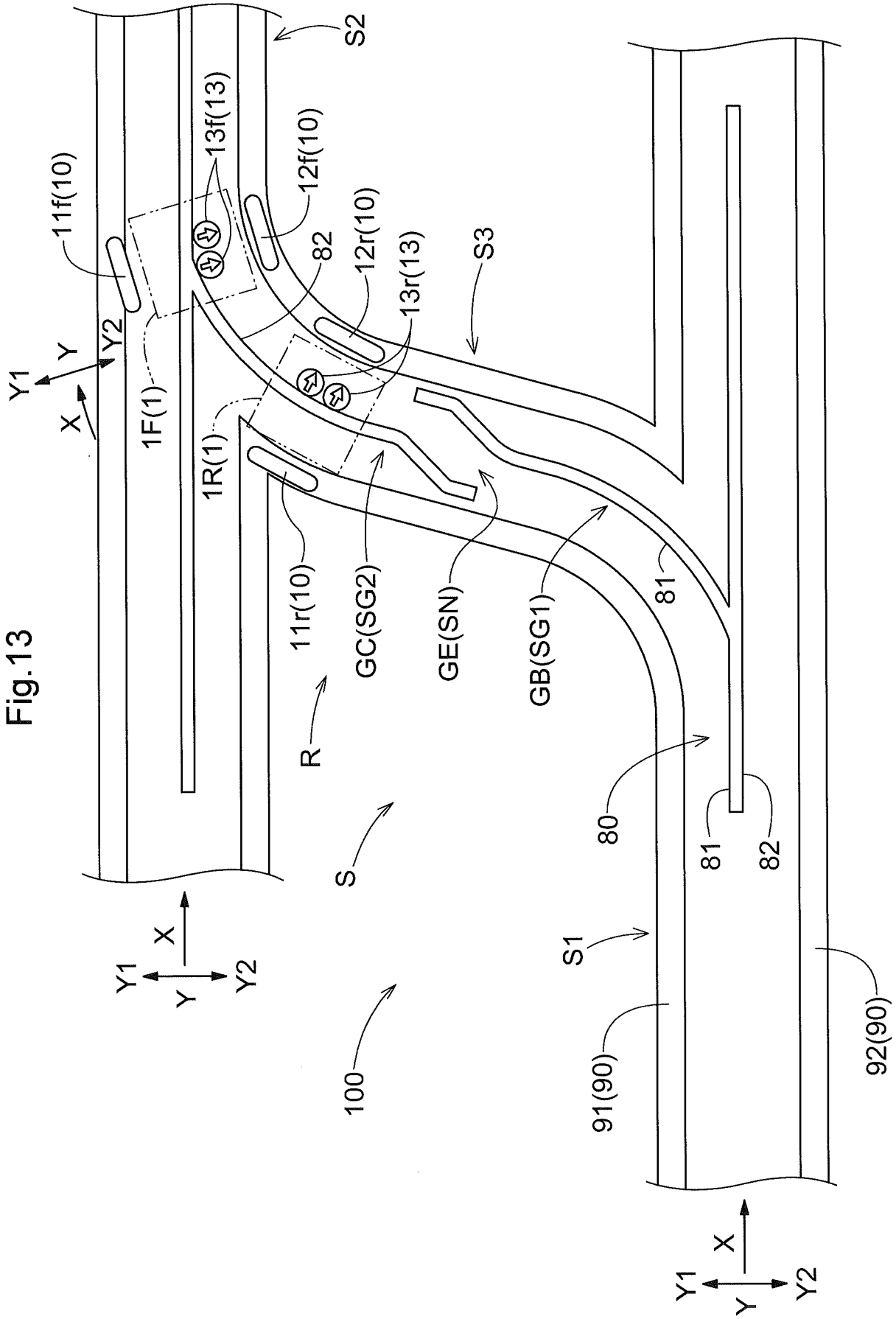

S2
11f(10)
13f(13)
12f(10)
12r(10)
82
13r(13)
S3
Y1
Y
Y2
X
1F(1)
1R(1)
11r(10)
GC(SG2)
GE(SN)
GB(SG1)
81
R
S
80
81
82
S1
91(90)
92(90)
100
X
Y1
Y2
Y

Fig.14

