mately parallel to the fixed plate **50** and a swing position at which it has swung clockwise from the non-swing position. The swing plate **46** is always urged toward the non-swing position by the urging force of a spring not shown.

[**0065**] Still further, the third cradle **45** axially supports a back portion of an actuation lever **57** via a pin axis **58** for free swinging. A pressing portion **57***a* which contacts the swing plate **46** is formed on the left-hand side of the actuation lever **57** as a boundary of the pin axis **58** while a notched portion **57***b* which is notched in a direction away from the swing plate **46** is formed on the right-hand side of the actuation lever **57** as a boundary of the pin axis **58**. In addition, an actuation projection **59** is disposed at the front end of the actuation lever **57**, projecting downward.

[**0066**] A left-hand side dog **60** and a right-hand side dog **61** which are attached to the bottom surface **2***b* of the case body **2**. The dogs **60**, **61**, when viewed in plan view, look like triangles whose vertexes **60***a*, **61***a* are central portions along the left/right direction. The dogs **60**, **61** are set such that they interfere with the actuation projection **59**, which moves in the left/right direction as the third cradle **45** moves in the left/right direction, and make the actuation projection **59** swing. Actuation of the actuation lever **57** will now be described.

[**0067**] First, as shown in **FIG. 10**, when the actuation projection **59** moving toward the left-hand side abuts with the dogs **60**, **61** from the right-hand side, the actuation lever **57** swings counter-clockwise, and therefore, the actuation projection **59** moves over the vertexes **60***a*, **61***a* of the dogs **60**, **61**. At this stage, because the notched portion **57***b* of the actuation lever **57**, swung counter-clockwise, is faced with the swing plate **46**, the actuation lever **57** will not act upon the swing plate **46** and the swing plate **46** is held at the non-swing position.

[**0068**] On the contrary, as shown in **FIG. 11**, when the actuation projection **59** moving toward the right-hand side abuts with the dogs **60**, **61** from the left-hand side, the actuation lever **57** swings clockwise. Therefore, the actuation projection **59** moves over the vertexes **60***a*, **61***a* of the dogs **60**, **61**. At this stage, the pressing portion **57***a* of the actuation lever **57** is swung clockwise to push the swing plate **46** and make the swing plate **46** swing at the swing position. As the swing plate **46** thus swings, the front ratchet arm **48** engaged with the ratchet gear teeth **44***c* of the front gear portion **44***a* of the rack **44** feeds the rack **44** one tooth.

[**0069**] When the actuation projection **59**, moving toward the left-hand side, passes over the dogs **60**, **61**, the swing plate **46** does not swing and the rack **44** therefore does not move vertically. Meanwhile, when the actuation projection **59**, moving toward the right-hand side passes over the dogs **60**, **61**, the rack **44** moves toward the back by one tooth and the movable unit **5** moves vertically toward the back together with the rack **44** as one unit. The amount of movement is set the same as one gap between the rows of the tactile pins **10** described earlier.

[**0070**] An abut member for reset **62** (**FIG. 12**) is attached to the bottom surface **2***b* of the case body **2**. The abut member for reset **62** is set such that when the movable unit **5** has moved toward the right-hand side to a stop position which will be described later, the abut member for reset **62** abuts with the front ratchet arm **48** and the back ratchet arm **51** and the ratchet arms **48**, **51** swing clockwise. As the ratchet arms **48**, **51** swing clockwise, the backstop parts **48***a*, **51***a* and the ratchet gear teeth **44***c* are reset, i.e., become disengaged from each other, the rack **44** is allowed to move toward the front, and the rack **44** moves toward the front when urged by the spring (**FIG. 12**).

[**0071**] A description will now be given about horizontal movements (movements along the left/right direction) and vertical movements (movements along the front/back direction) of the movable unit **5** and a relationship between the first to the fourth photosensors **37** through **40**, the left-hand side and the right-hand side dogs **60**, **61** and the abut member for reset **62**.

[**0072**] First, before the motor **25** starts moving, the front and the back ratchet arms **48**, **51** abut with the abut member for reset **62**, and the backstop parts **48***a*, **51***a* and the ratchet gear teeth **44***c* of the rack **44** are reset, i.e., are disengaged from each other. At this stage, the rack **44** is located at the front-most position, and the movable unit **5** is set such that the n-th actuation pin **16** (n=1 through 8) comes to the right-hand side to the tactile pin **10** which is in the first column and the $\{(n-1)\times 6+2\}$-th row when the rack **44** is at the front-most position. Meanwhile, the actuation projection **59** comes to the right-hand side of the right-hand side dog **61**.

[**0073**] Next, as the control part **8** outputs a start-up command, the motor **25** drives the movable unit **5** and the vertical movement mechanism **7** toward the left-hand side. As this occurs, the front and the back ratchet arms **48**, **51** move away from the abut member for reset **62** and swing counter-clockwise owing to the urging force of the springs **53**, **54**, and the backstop parts **48***a*, **51***a* engage with the front-most ratchet gear teeth **44***c* of the front and the back gear portions **44***a* and **44***b*. Further, before the actuation pins **16** reach the tactile pins **10** belonging to the first column, the actuation projection **59** passes over the right-hand side dog **61**. On this occasion, because the actuation projection **59** is moving toward the left-hand side, the movable unit **5** does not move vertically. After the actuation projection **59** has passed over the right-hand side dog **61**, the actuation pins **16** reach the tactile pins **10** belonging to the first column and move further to the left-hand side toward the tactile pins **10** belonging to the 64-th column, during which the third photosensor **39** detects the timing of turning on of the solenoids. Based on the timing detection signal from the third photosensor **39** and an image information signal from the host computer PC, an ON-command is fed to selected ones of the solenoids **4**, the actuation pins **16** move upward and make the corresponding tactile pins **10** move to the upper movable positions. As the actuation pins **16** pass beyond the tactile pins **10** belonging to the 64-th column, the actuation projection **59** passes over the left-hand side dog **60**. At that time, because the actuation projection **59** is moving toward the left-hand side, the movable unit **5** does not move vertically. After the actuation projection **59** has passed over the left-hand side dog **60**, the fourth photosensor **40** detects the left-hand side reverse position and the motor **25**, after stopping once, drives to move the movable unit **5** toward the right-hand side.

[**0074**] As movement to the right-hand side starts, first, the actuation projection **59** passes over the left-hand side dog **60**. On this occasion, because the actuation projection **59** is