Merge and assemble the robotic arm via

Solid works

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**[19-6-2021]**

**preamble**

The degree of freedom (DOF) is an important concept in robotics. In general, each degree of freedom is a ***joint***, which can be controlled along with the other ***joints*** to have a particular arm position. Also, each DOF requires a motor.

**Components :**

1 – Base

2 – Wrist

3 – Two links

4 – Two joints

5 – Gripper

**Installation process**

To begin with, place the bottom of the arm base on a straight platform. Next set the wrist on the upper part of the base to freely rotate 360 degree around the axial base. Then join the link 1 (as shown in the picture below) with the wrist. Simillarly, fasten joint-link1 with joint-link2. Finally, connect the gripper at the end of joint-link2.

A picture containing tool, scissors

Description automatically generated

Gripper

Base

Wrist

Joint-link2

Joint-link1