

Assembly instructions: motor holder

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Overview testbed

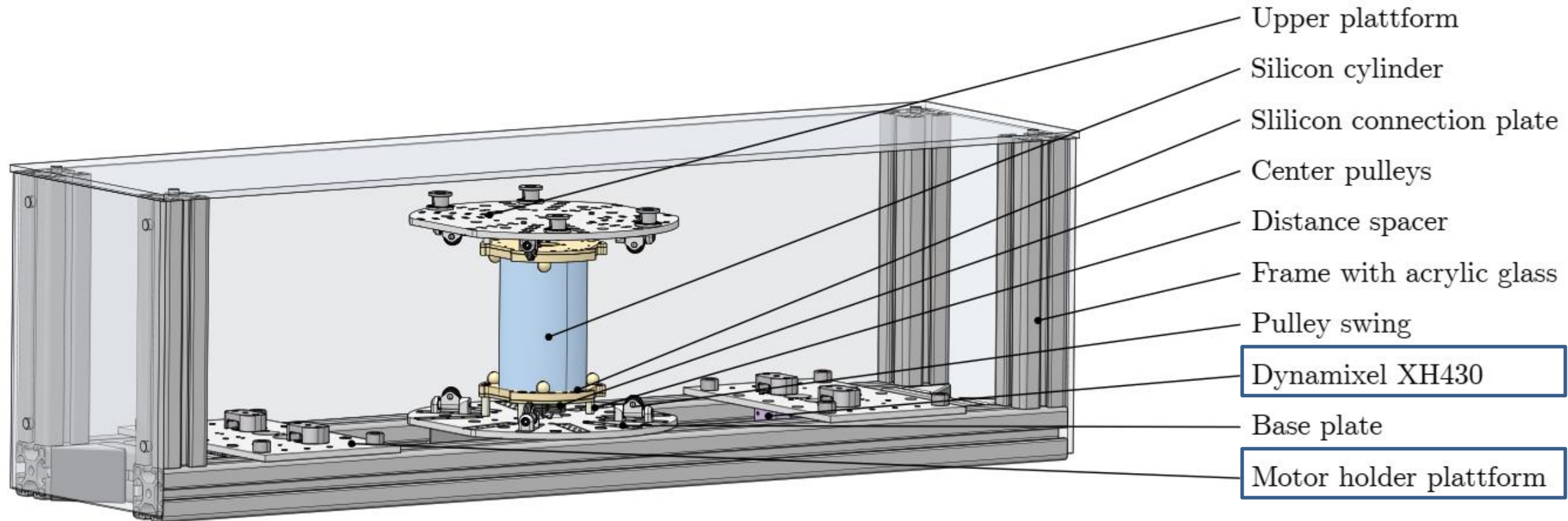
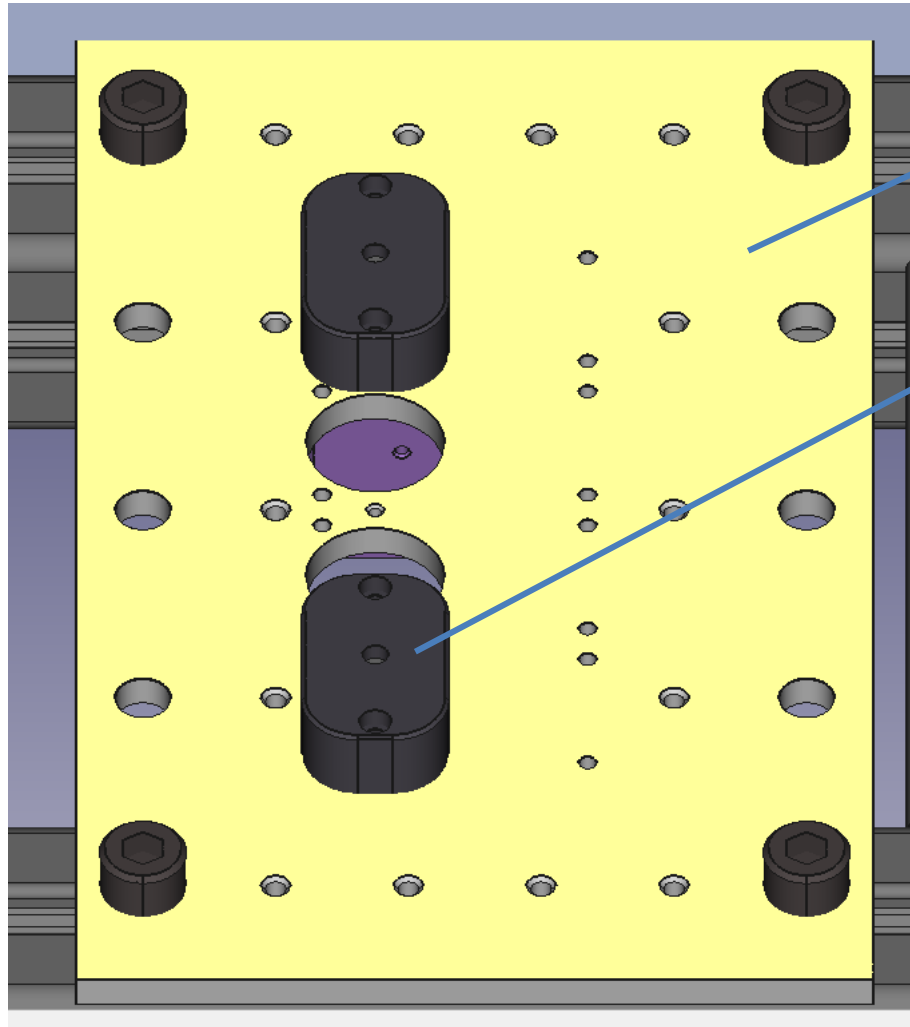


Fig. 2: Overview of the proposed open source tendon-driven continuum mechanism with all involved components.

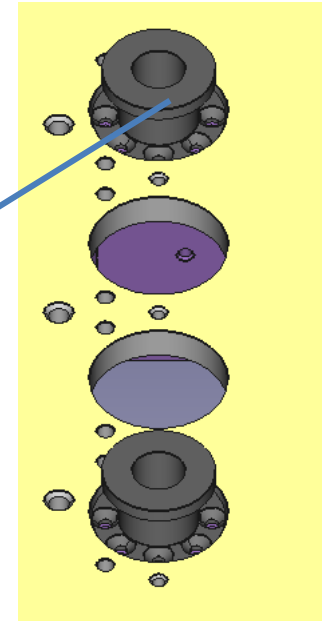
Overview of motor holder



TDC_NECK_ACTORS_PLATE

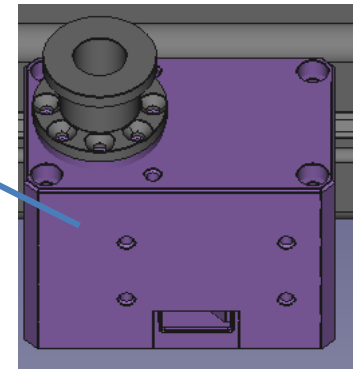
TDC_SIMPL_ELAST_WHINCH

TDC_NECK_TENDON_STOP



Dynamixel X-430

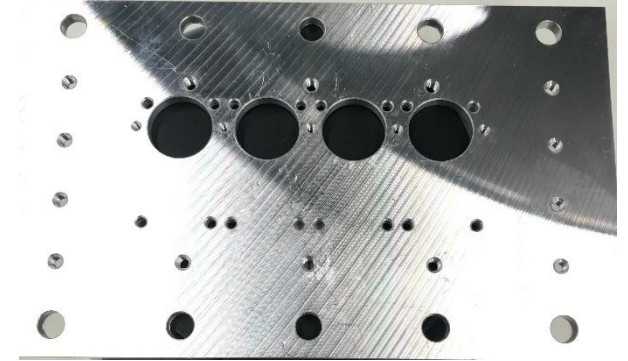
Cylinderhead screw M8x22



Components

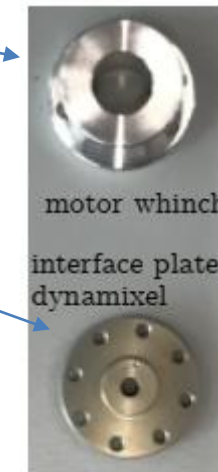
Manufacturing parts

- 2x motor holder plater (TDC_NECK_ACTORS_PLATE)
- n_t tendon winches (TDC_SIMPL_ELAST_WINCH)
- N_t Tendon stops (TDC_NECK_TENDON_STOP)



Off-the-shelf parts:

- n_t Dynamixel motors with interface plate
- 4xn_tx M2.5x12 (mount Dynamixel on holder)
- 4xn_tx M2x4 (mount winch on Dynamixel interface plate)
- n_tx M2x6 (mount interface plate on Dynamixel output shaft)



Tools:

- Allenkey

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Instructions:

- Mount each of the n_t winches onto the Dynamixel interface plate using 4xM2x4 cylinderhead screws
- Connect each Dynamixel interface plate with the output shaft of a dynamixel motor using M2x6 cylinderhead screw
- Mount each of the n_t dynamixel motor with 4xM2.5x12 cylinderhead screw to the actuator plate
- Mount each of the n_t tendon stops onto the motor holder plate

