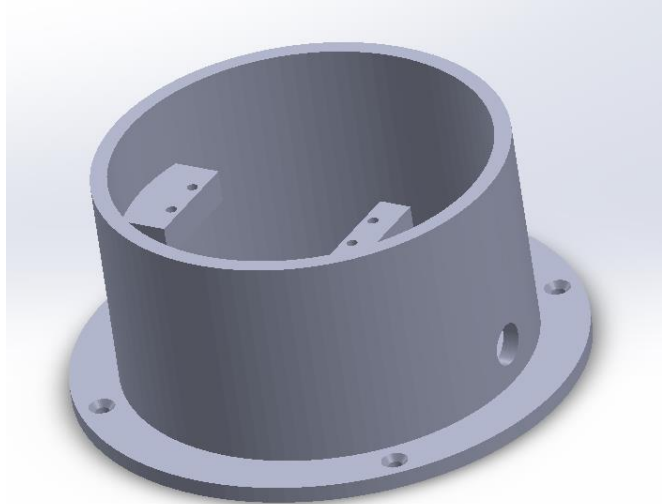


Hello, the robot arm was installed using SolidWorks Software and in this report I will talk about the installation method with pictures.

But first, let me talk about the 5 pieces of the robot arm, which are:

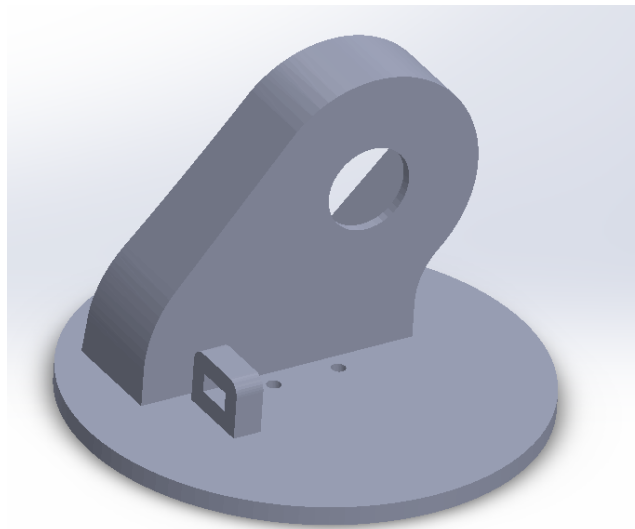
1- Base

Represents the base of the arm.



2- Waist

Represents the cover above the base.



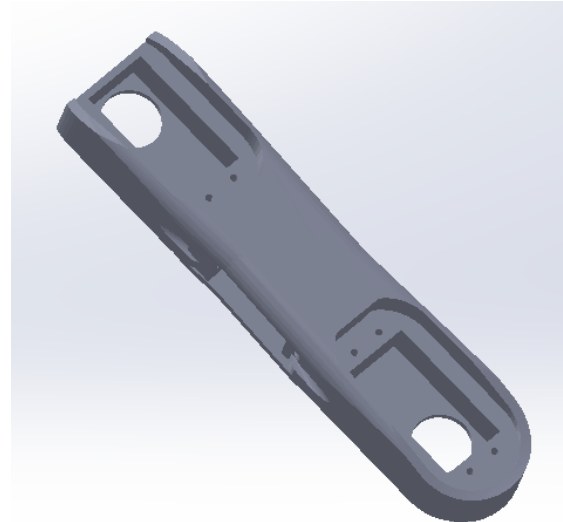
3- Arm 1

Represents the first connection in the arm.



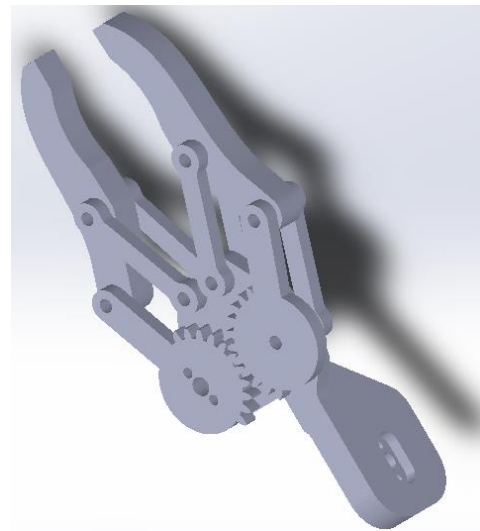
4- Arm 2

Represents the second connection in the arm.



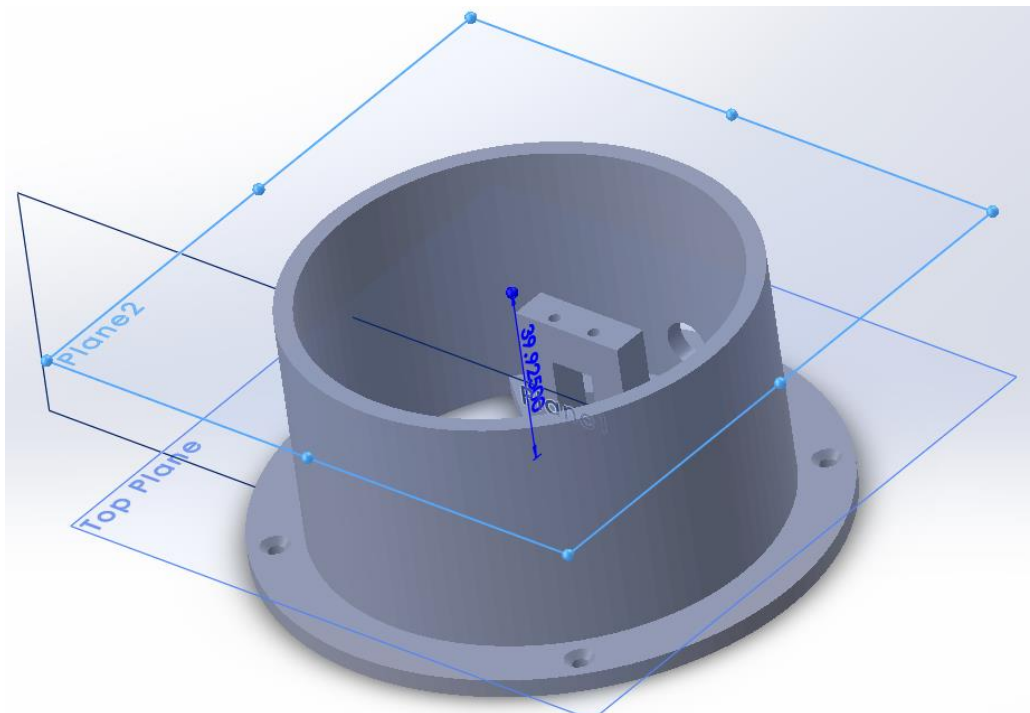
5- Gripper

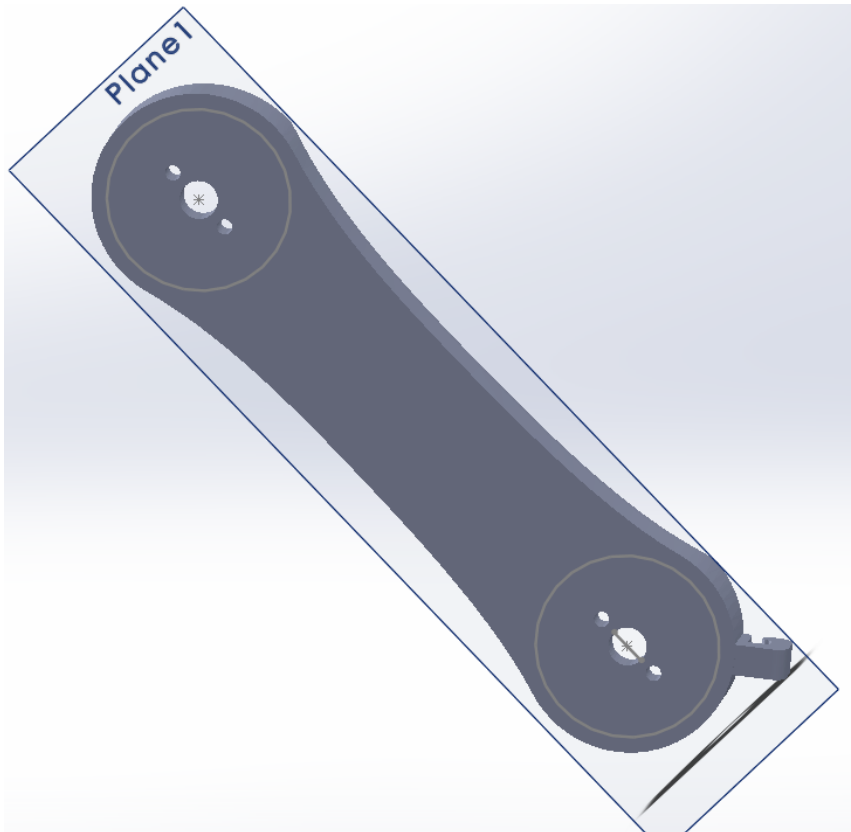
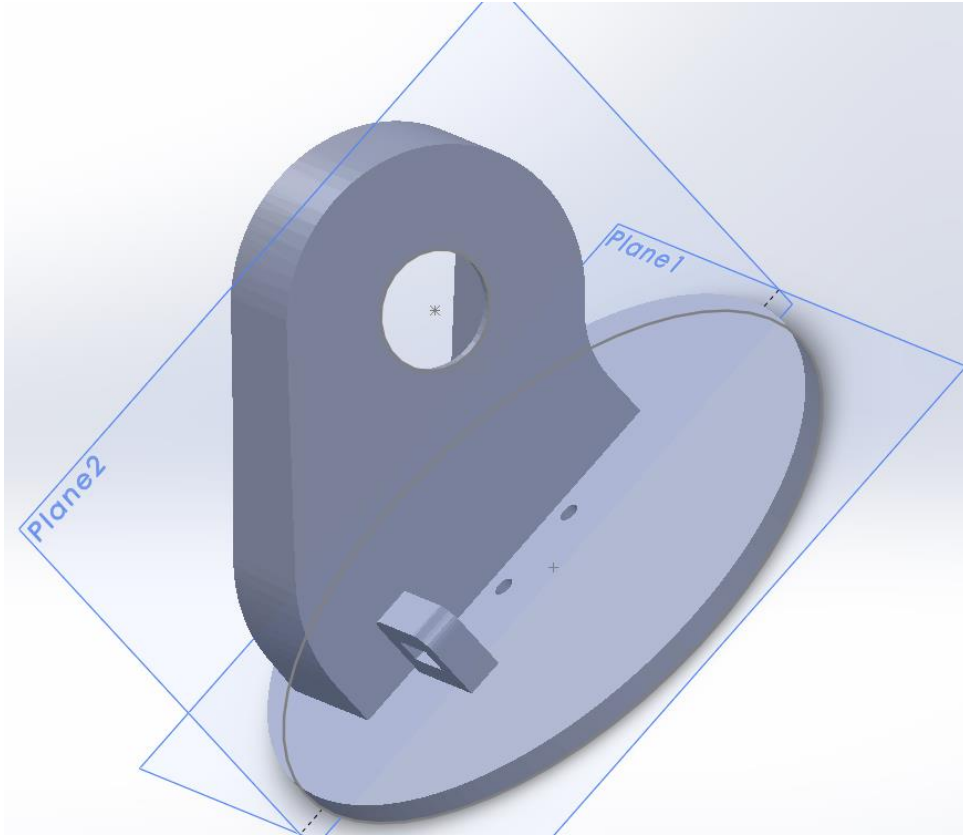
Represents the end effector of the robot arm

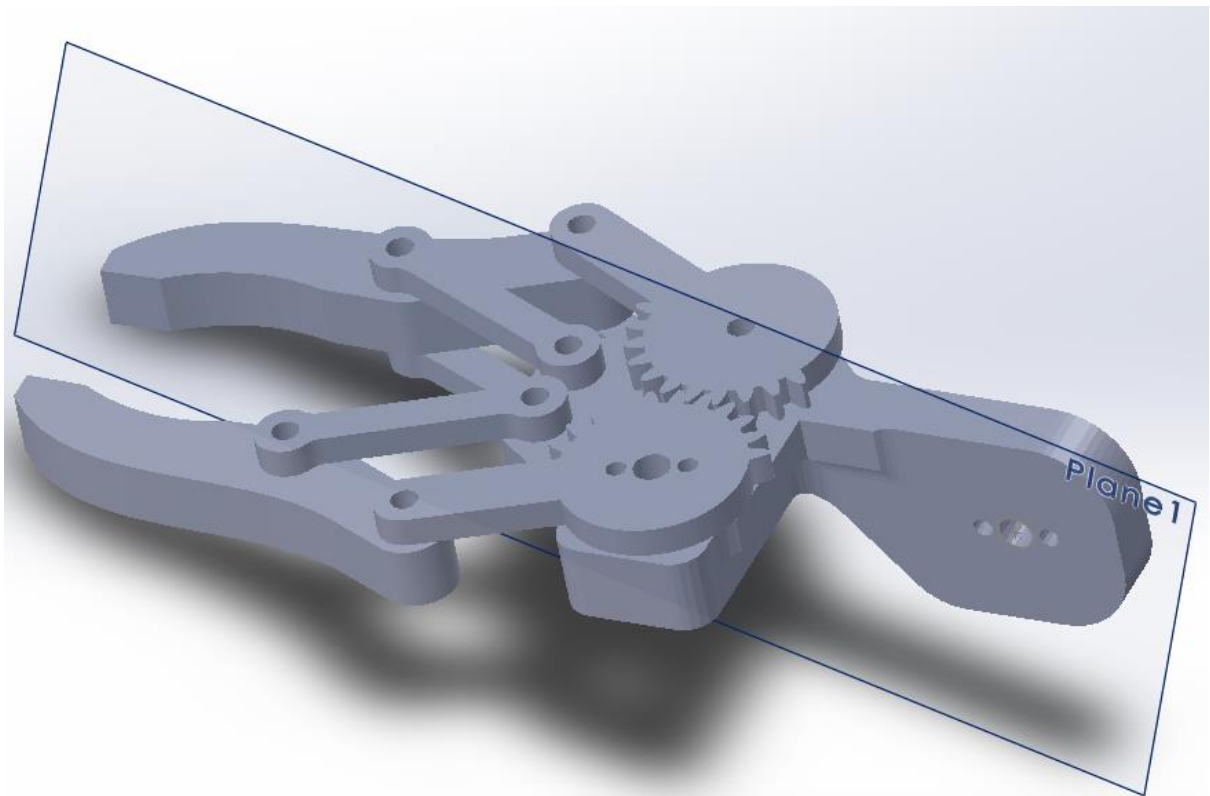
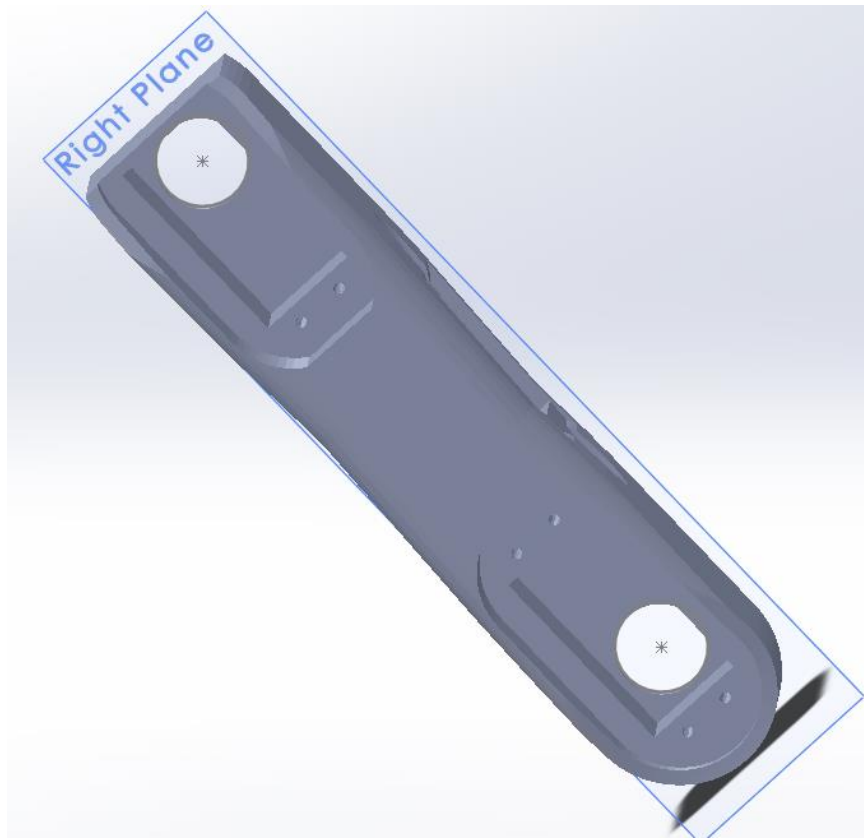


Now we will talk about installation in SolidWorks:

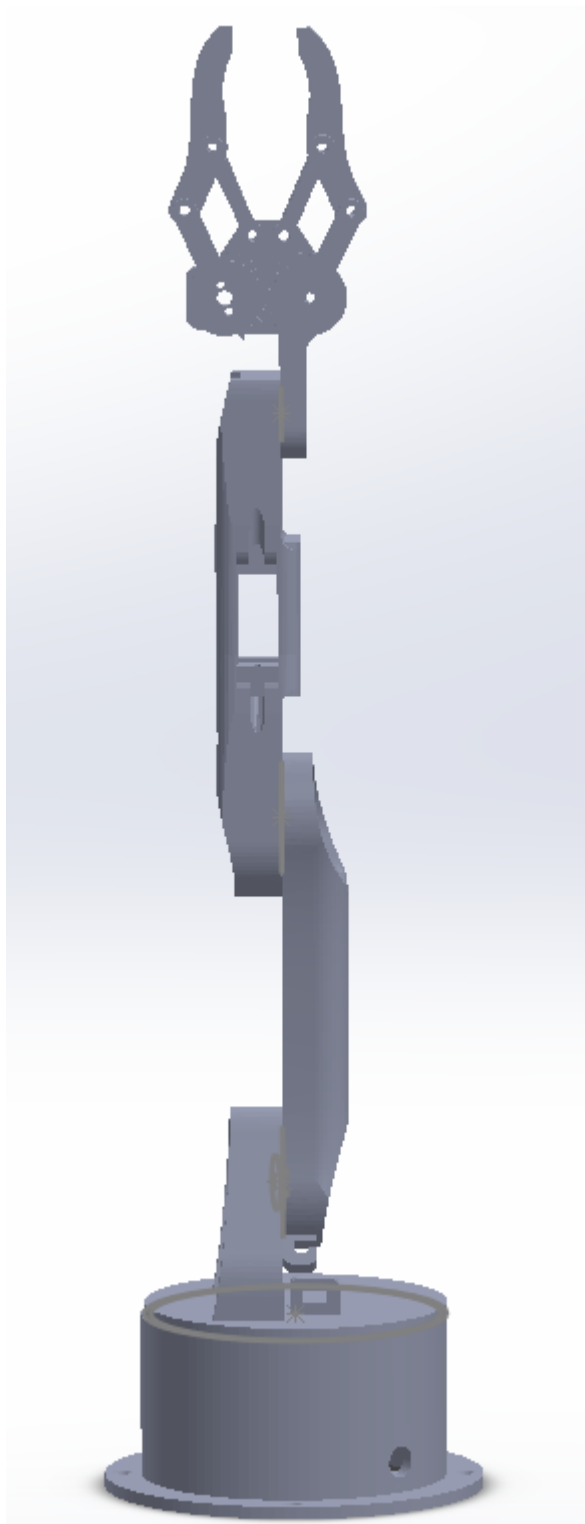
At first, we cannot easily link STL files together in SolidWorks, so the correct way to install is to put a new Plane in the linking position, Also sketch on the plane to make the mate. like the following images::








Now mate is done easily using mate relationships.



- ▼  Mates
- Concentric12 (Waist<1>,Sketch5)
 - Coincident7 (Waist<1>,Sketch5)
 - Concentric15 (Waist<1>,Arm 01<1>)
 - Coincident8 (Waist<1>,Arm 01<1>)
 - Concentric16 (Arm 01<1>,Arm 02<1>)
 - Coincident9 (Arm 01<1>,Arm 02<1>)
 - Concentric17 (Arm 02<1>,Gripper e<3>)
 - Coincident10 (Arm 02<1>,Gripper e<3>)

