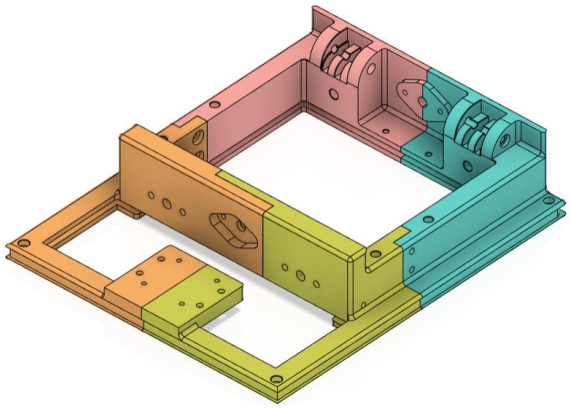
Hendrikse Jérémy

Session report 10

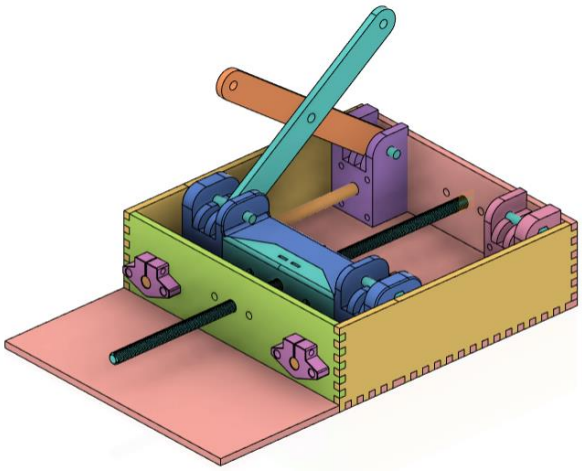
Before the session:

Before the session I've did quite a lot of work, there was a lot of things that had changed compared the 3D model I first made. Replaced the grabbing stepper by a bigger one, changed the lift stepper by a DC motor, creating a prototype PCB that also needed a place on the robot and also Julius had done it's first prototype and I was quite larger and longer than mine (app 5cm). I also wanted to have replace that ugly looking and not strong CP5mm. I decided to start a new 3D model that would look the same as the Julius's idea, one 5mm Plexi plate with a 3D printed frame around it. This design would also make it easier to include directly in the print some parts that where up to today printed and screwed to the wood.

I ended up the model we can see under on the left that will replace the old model on the right. The new version is made from 4 3D printed parts hold together by screws and a plexi plate that will go in the middle. On the latest version each color represents one whole part.



New Design

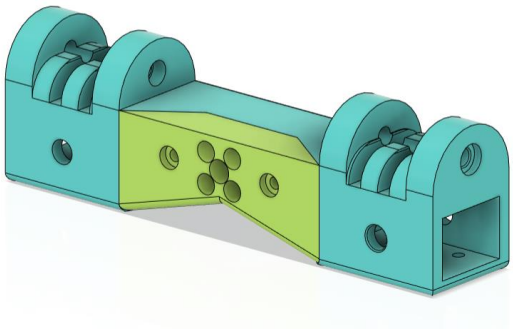


Old Design

During the session:

During this session I redesigned the slider that we can see in dark and light on the Old Design image on the prototype I was currently using there was some problems with the fixation of the

lattice the screws where difficult to tighten. I also had slightly changed the fixation of the lattice on the frame because there was one small issue making it impossible to lower the lift completely. On the image bellow we can see the new prototype that is only missing the fixation for the limit switch that will be fixed on top of it.



New slider prototype