

Robot Installation Instructions Right Hand

Parts List

First finger joint	5 including thumb 1
Second finger joint	5 including thumb 1
Third finger joint	5 including thumb 1
Palm	1
Palm 1 connector	1
Guard	1
Front tie rod	5
	Contains thumb 1
Middle tie rod	5
	Including thumb 1
Pull-up rod support	5
Lower rod support	5 included
	1 counter support with thumb
Anti-burning servo	6

Steering gear control

The recommended range is 1.00 -2.00, corresponding to 0 to 180 degrees of the servo.

Servo voltage 5 to 6 volts Servo line sequence : brown wire power negative , red wire power

Gensho , Yellow

(Orange) line control signal. Servo control coordination?

The recommended range is 1.0 5-2.0 15 , corresponding to 0 to 180 degrees of the servo.

Write your own program

PWM
The range should be determined first to ensure that it does not exceed the limit before connecting the control

Steering gear.

Otherwise, the over-limit impact wave will cause the servo angle to lose control and may be damaged instantly.

Servo gear.

Spiral tube

Section 1

1V12 cut 2 screws

8 sets

1712*10 screws

20 sets

1712*6 screws

8

1713*14; screw	16
5mm diameter bronze bearing	16
1V13 pad	20 items
IV! 3 anti-slip nuts	18
Cross countersunk head 1 2*10 screw	15
1V12 pad	25 items
IV! 2 anti-slip nuts	20 items
IV! 3*15 double-pass copper column	2 items
1 13*10	15 sets
1 13*9	6
Fixed set	10

Long spring

5

Short spring

5

Copper Sliding Bushing

5

1712*6 self-tapping screws

10

One-line swing arm

5

1712.5*6 screws

8

Tie rod

5

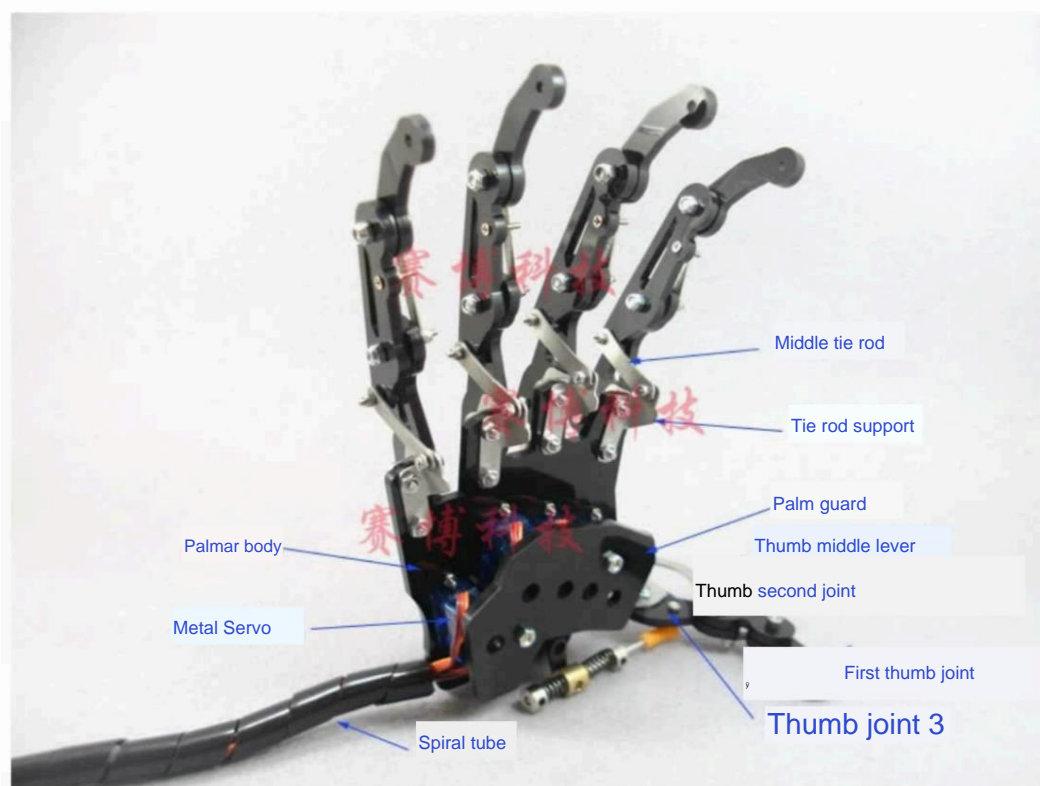
Spherical parts

5

1.5 hexagon wrench

1





Spring washers are used in the fastening parts, and flat washers are used in the rotatable joint parts.



Index finger, middle finger, ring finger, and little finger second joint parts.

The left screw is a 2*12 cross countersunk screw. Pass through from bottom to top and use a spring

Anti-loosening pad, add 1/12 nut to fix.

The middle screw passes from top to bottom. The order of parts is : 1712*10 cross countersunk screw , second joint accessories , /12 flat washer, rear pull rod, 1 2

Anti-slip cap.

The installation requirement is to press the two accessories until they can rotate freely. The

right screw passes from top to bottom. The order of parts is : 1712*8 screws,

1712 flat pad, rear pull rod, 1712 flat pad, 1712 anti-slip cap.

The installation requirement is to press the two accessories until they can rotate freely.



Thumb second joint parts

The left screw is a 2*12 cross-sunk head. Pass it from bottom to top and use the spring

Anti-loosening pad, fixed with 1712 nut.

The right screw goes through from top to bottom. The order of parts is : 1712*10

Countersunk screw , thumb joint accessories , 1712 flat washer, middle finger

Pull rod, /12 anti-slip cap. The

installation requirement is to press the two accessories until they can rotate freely.



Install neatly as shown in the picture and keep ready for use.



Index finger, middle finger, ring finger, little finger , 1st joint part, 3rd joint part

Piece.

The left screw goes through from bottom to top, the order of parts is : 1 2*10 10

Countersunk screw , 1st joint finger accessories , 1712 flat washer, middle tie rod,
1V12 non-slip cap.

The screws on the right side pass from bottom to top. The order of the parts is : 1712*10

Cross countersunk screw , third joint finger accessories , 1\2 flat washers, middle pull
Rod, 1712 non-slip cap.

The installation requirement is to press the two accessories until they can rotate freely.



Thumb 1st joint component, 3rd joint component.

The left screw goes through from bottom to top, the order of parts is : 1712*10

Countersunk screw , 1st joint finger accessories , 1\2 flat washers, middle tie rod,
1V12 non-slip cap.

The right side screws pass from bottom to top, the order of parts is : 12*10

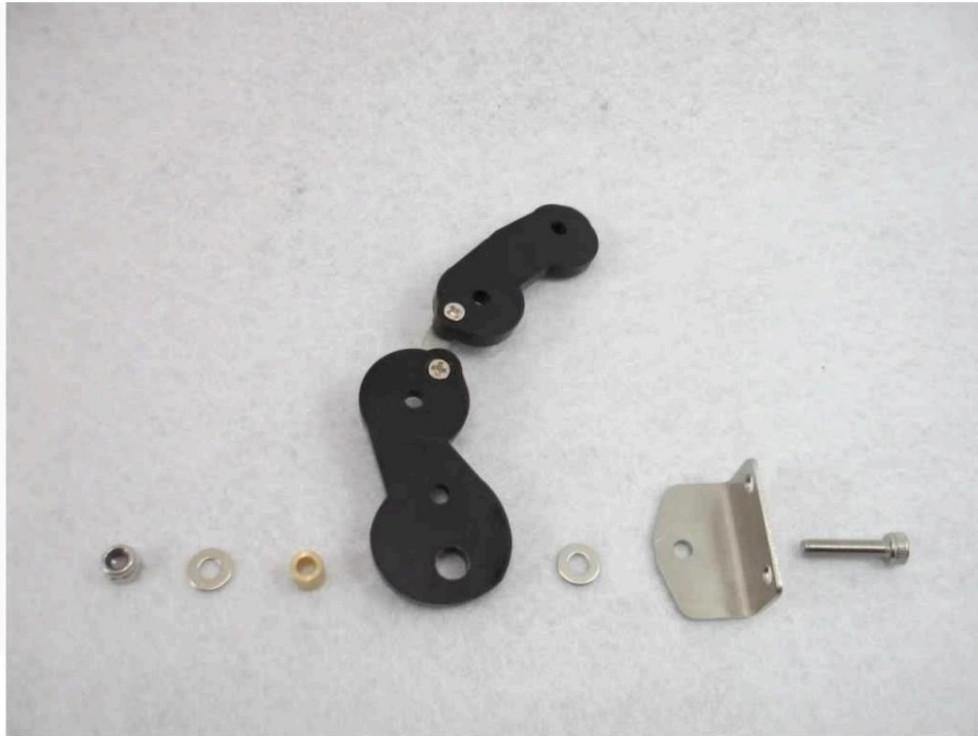
Cross countersunk screw , third joint finger accessories , /12 flat washer, middle pull

Rod, 1712 non-slip cap.

The installation requirement is to press the two accessories until they can rotate freely.



Install neatly as shown in the picture and keep ready for use.



Install the thumb mount, paying attention to the orientation.

The first screw on the bottom is inserted from right to left. The order of the parts is :

Hexagon socket 1713*12 screws, fixing bracket, 1713 flat washer, thumb 3

Joints, copper bearings, 1/13 flat washers, non-slip caps.

Installation requires tightening.



Install the fixing base on the index finger, middle finger, ring finger and little finger, paying attention to the direction.

The first screw on the left is inserted from right to left. The order of the parts is :

Hexagonal 1713*12 screws, fixing bracket, 1713 flat washer, finger 3rd level

Section, bronze bearing, 1713 flat washer, 1713 anti-slip cap.

Installation requires tightening .



Install neatly as shown in the picture and keep ready for use.

5, 12:29





Install them together, screwing them from bottom to top.

The order of the parts on the left is: 1713*14 hexagon socket screws, finger first

Three joints, flat washers. Second finger joint, copper bearing, /13 flat washers,

1V13 non-slip cap.

The order of the right link parts is: 1713*14 hexagon socket screws, finger first

1st joint, 1713 flat washer. 2nd finger joint, copper bearing, M3 washer,

M13 Anti-slip cap.

Installation requires tightening.



The order of the parts on the left is: 13*14 hexagon socket screws, finger first

Third joint, 1713 flat washer. Second finger joint, bronze bearing, 1713 flat washer,

1713 Anti-slip cap.

The order of the parts on the right is: 1713*14 hexagon socket screws, finger first
1st joint, 1713 flat washer. Second finger joint, copper bearing, flat washer,
1713 Anti-slip cap.

The installation requirement is to press the two accessories until they can rotate freely.



Combine the fingers and assemble the installed palm part with the
palm. Use 1713*10 hexagon socket screws to connect with the palm.

The order is 1713*10 hexagon socket screws , upper finger seat,
palm, lower finger seat, nut. Tighten.

Install the ball tie rod as shown below. Use the yellow joint

The pull rod screw is made of copper and is more precise in screwing.

It is easy to slip when installing. You can first click 502 and then install

Install , put a little glue on the screws.

Then penetrate the small hole.







Installing the thumb is the same as above.







Install the servo and fix it with 2*10 screws.

The position should be at 90 degrees.

Installation of joint sliding copper sleeve.

Install the palm guard using four 3 *9 screws

1/13*15 double-pass copper column

2 pieces to fix the guard to the palm

Above.

There are 3 holes on the rudder muscle.

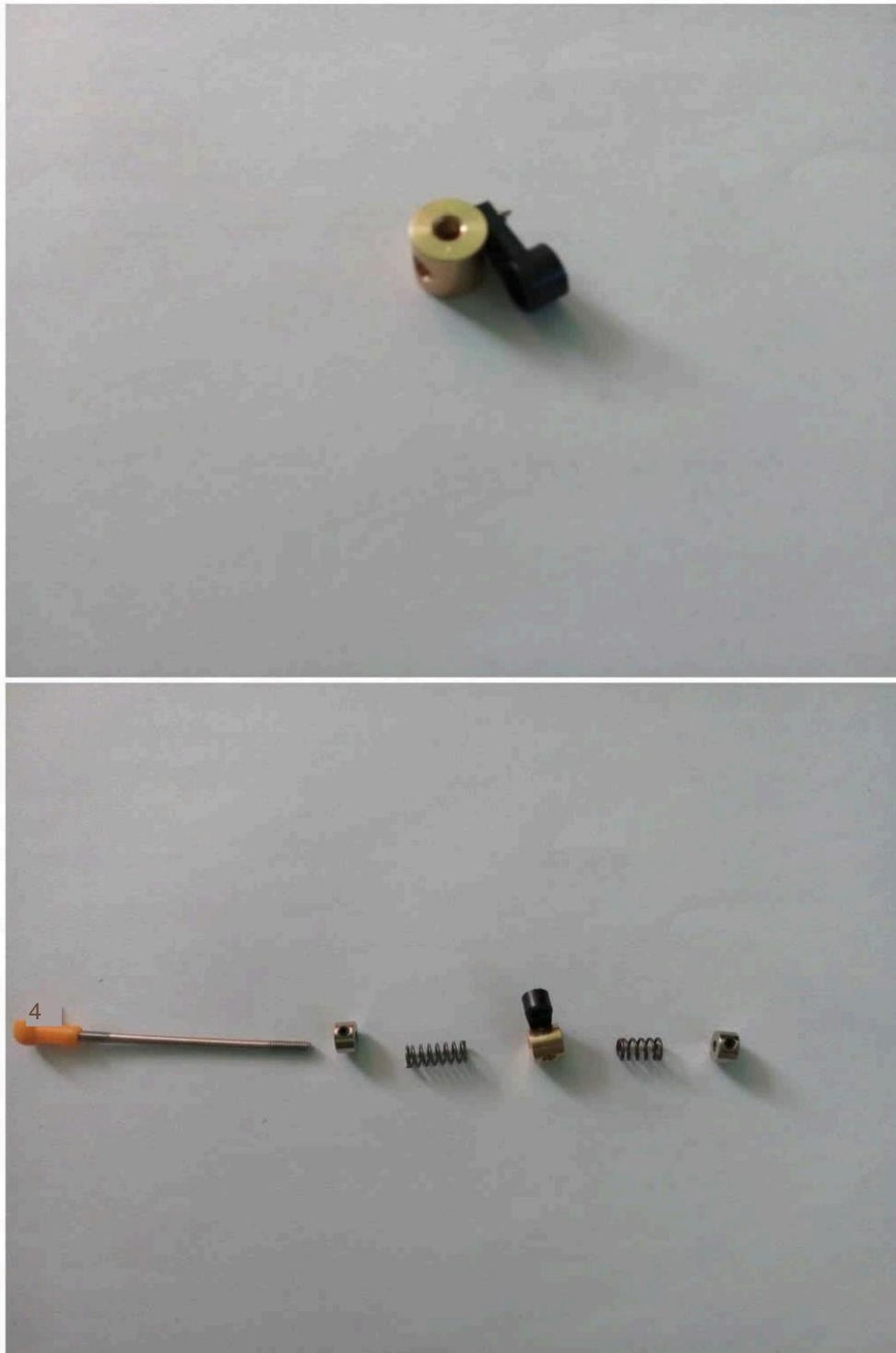
The current market is called I point to grab the heron

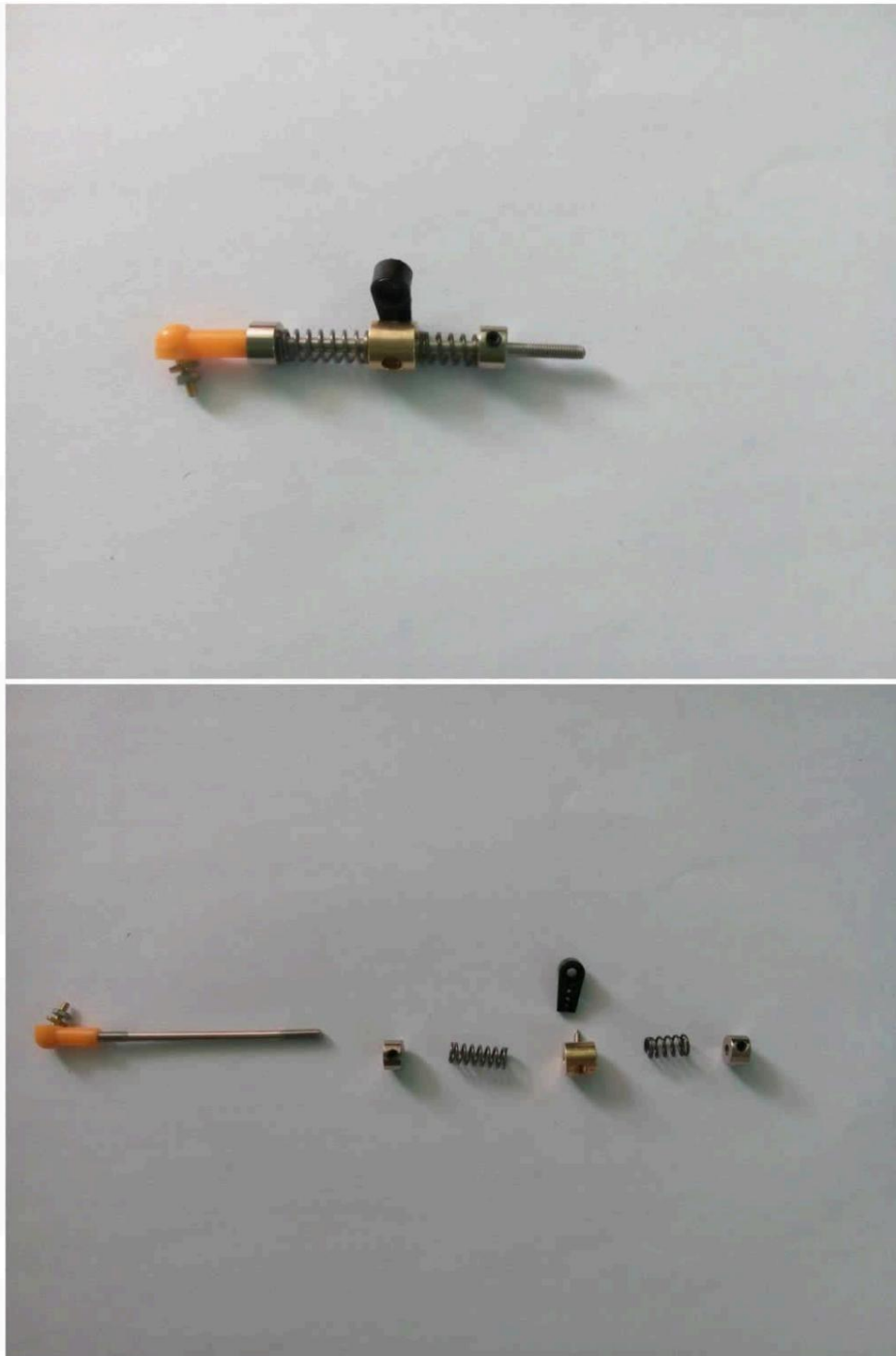
Shi wrote two Kongs,

Outermost hole of the bin, high axis 1111

The farthest hole.







Adjust the position of the joint fixing sleeve to adjust the mechanical finger

The initial position of .

