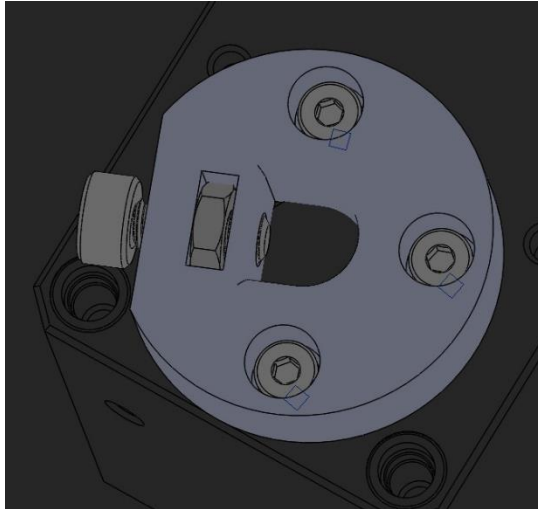
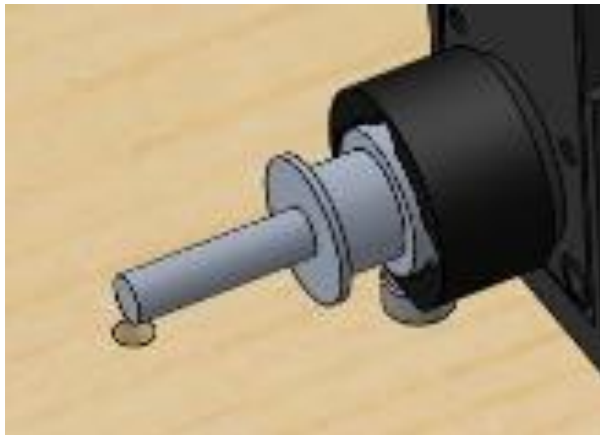


1.COUPLER MOTOR

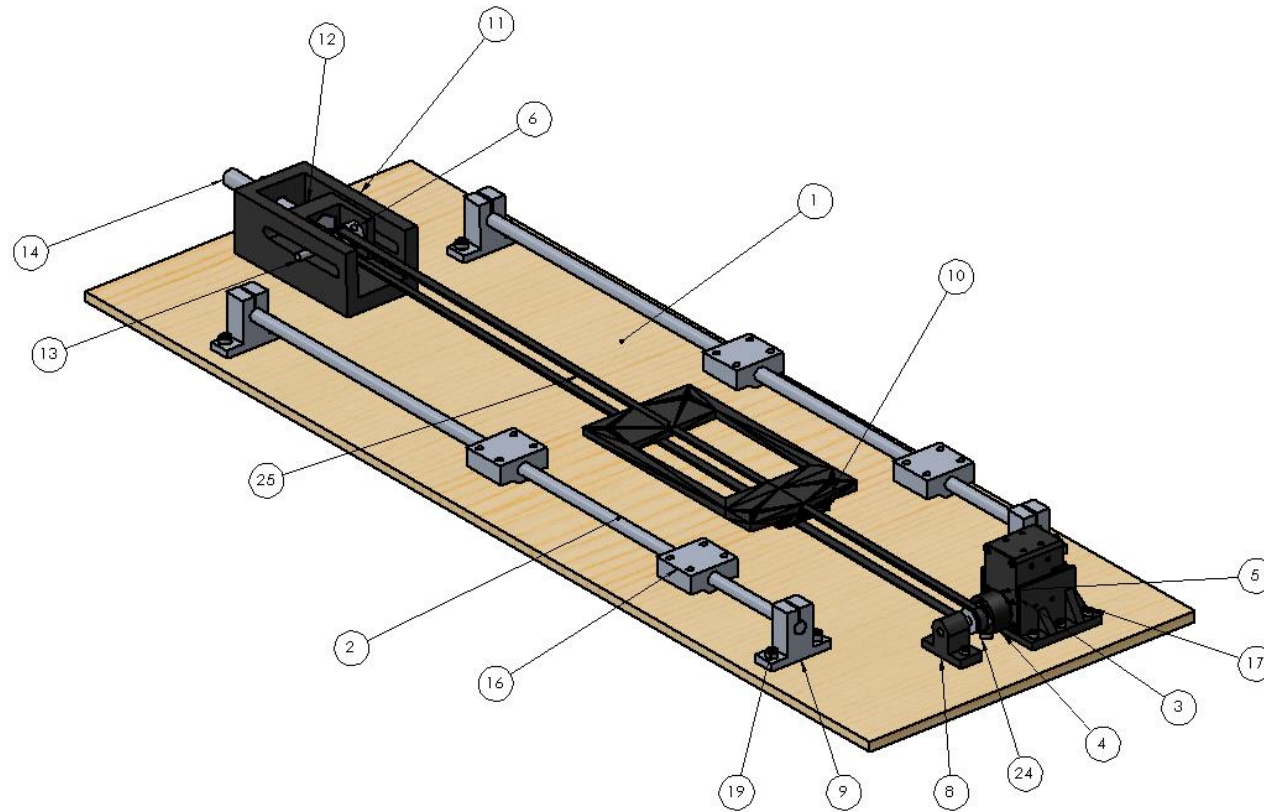
- Insert a nut in one coupler joint 2 and in two coupler joints 3
- Bolt the coupler joint 2 on a W250 Dynamixel motor and bolt each coupler joints 3 on a W350 Dynamixel motor



- Bolt the coupler pulley into a W250 Dynamixel motor
- Insert the shaft in the pulley and tighten it with a bolt through the pulley coupler

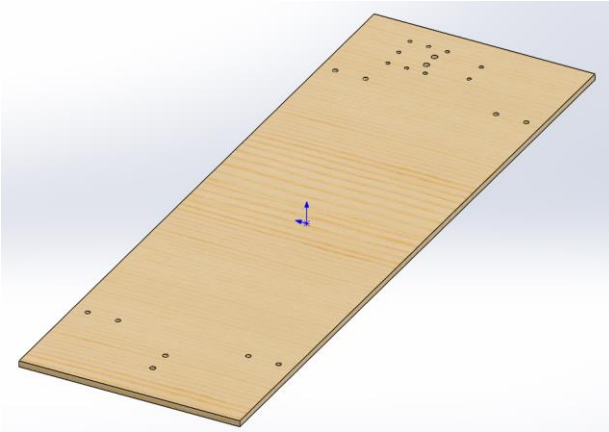


2.LINEAR AXIS

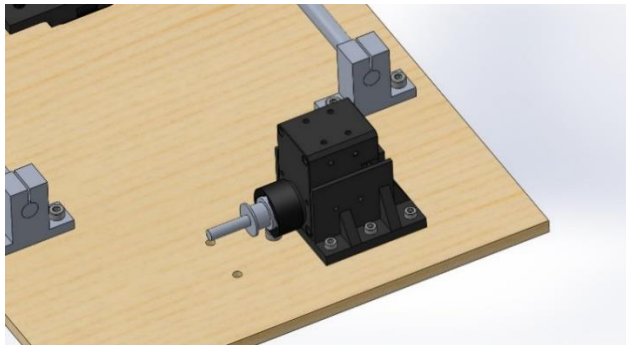
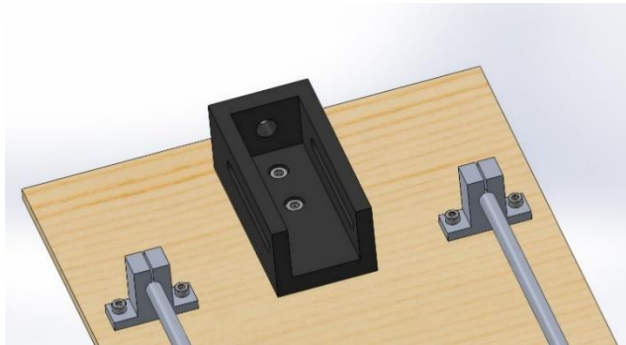


No. ARTICLE	NUMERO DE PIECE	QTE
1	plate	1
2	rail	2
3	XL430-W250	1
4	motor_case	1
5	coupler_pulley	1
6	pulley	2
7	91292A832	3
8	pulley_axis_support	1
9	rail_support	4
10	coupler_timing_belt_base	1
11	tensioner_fixed_part	1
12	tensioner_moving_part	1
13	pulley_long_shaft	1
14	M10-75mm TYPE 18-8 SS HEX HEAD CAP SCREW	1
15	M10-NUT TYPE 18-8 SS THIN HEX NUT - DIN 439B (1)	1
16	linear_bearing	4
17	91292A115	9
18	90710A030	9
19	91292A118	8
20	91292A118	2
21	90710A035	8
22	90710A035	2
23	pulley_shaft	1
24	91292A108	1
25	timing_belt	1

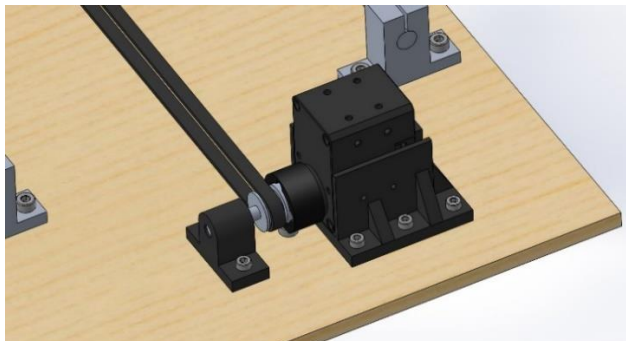
- Laser cut a 300 mm x 700 mm x 6.35 mm plywood



- Fix each part with bolt and nut



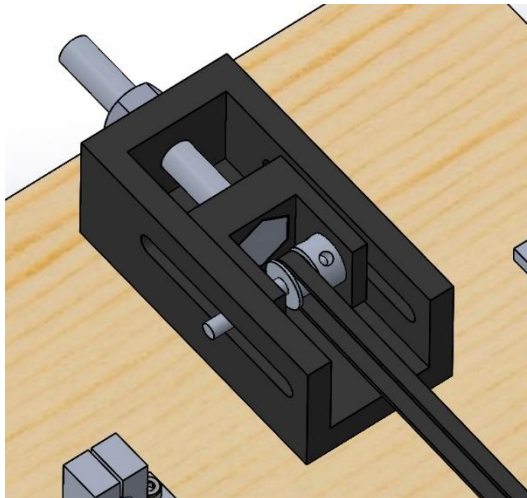
- Put the timing belt, then the support axis pulley



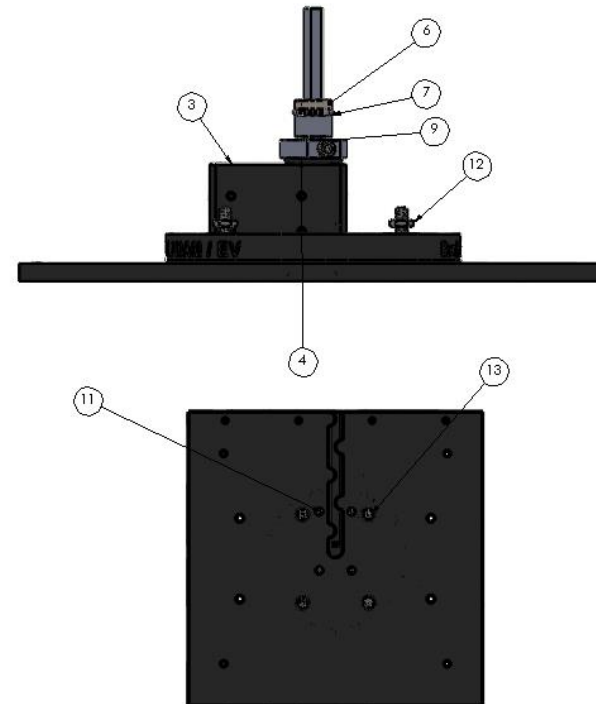
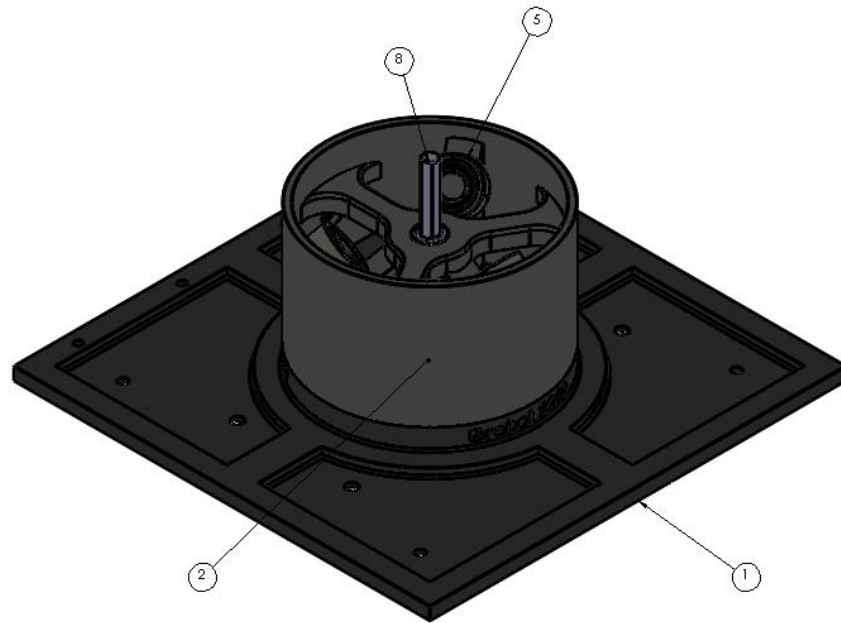
- Fix the timing belt to the base coupler with tie wraps



- Assembly the belt tensioner
- Pass the timing belt around the belt tensioner pulley and fix it on the timing belt base coupler

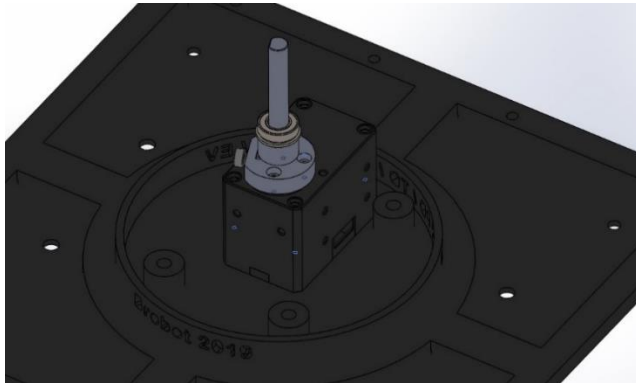


3.SOCLE

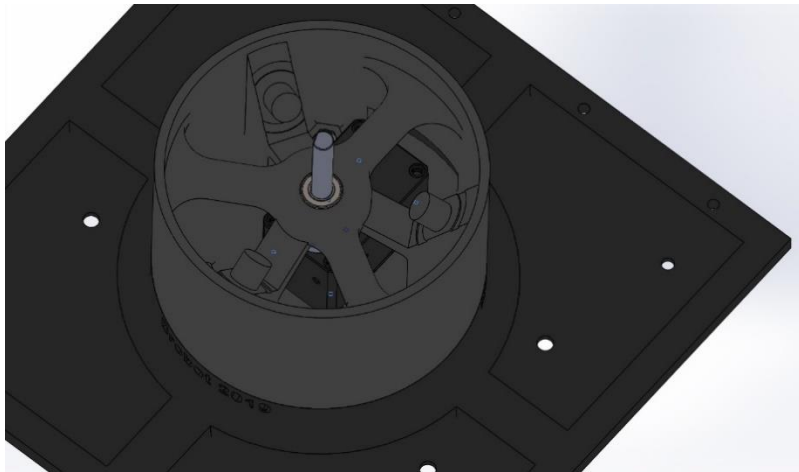


No. ARTIC LE	NUMERO DE PIECE	QTE
1	robot_base plate	1
2	Support_Be aring_V4	1
3	XL430-W250	1
4	Coupler_Joi nt1	1
5	bearing	3
6	535198	1
7	6432K12	1
8	shaft	1
9	91292A112	1
10	90710A030	1
11	91292A002	4
12	90710A035	4
13	91292A118	4
14	91292A832	3

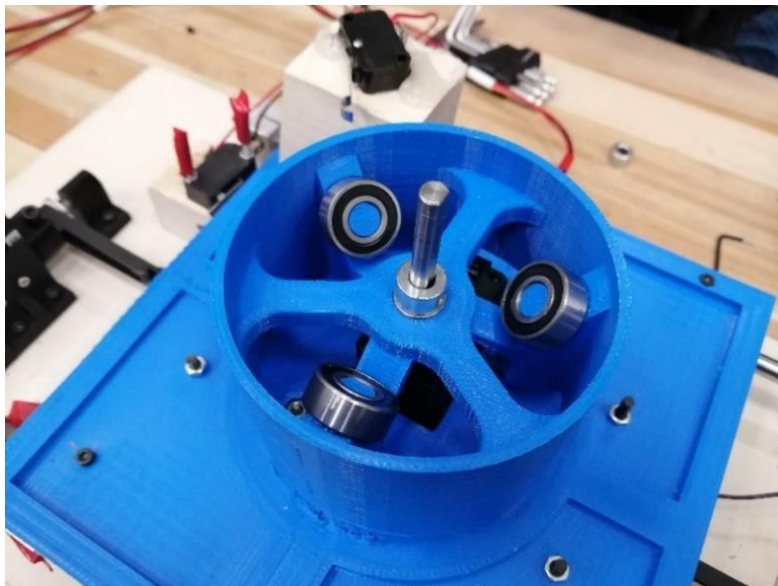
- Fix the dynamixel motor on the robot base plate
- Fix the shaft on the motor coupler with bearing on the shaft



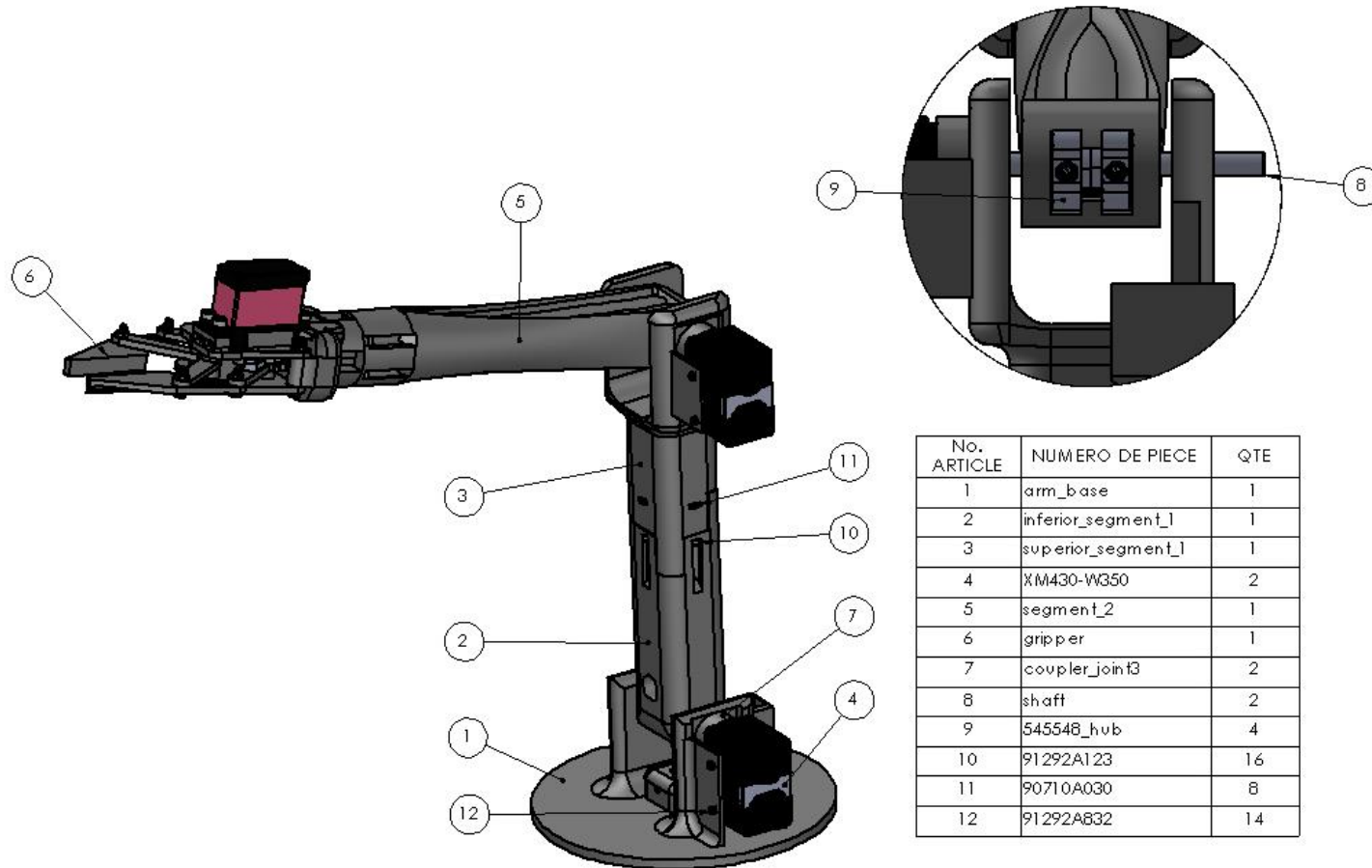
- Fix the bearing support on the base plate



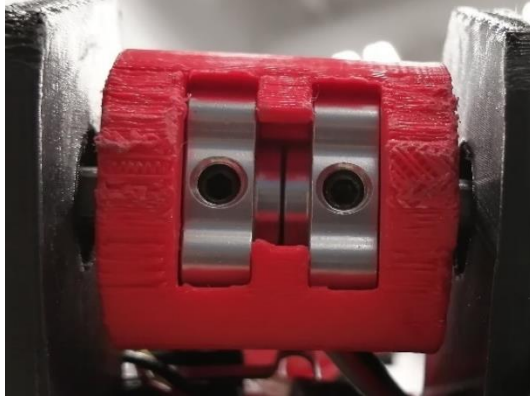
- Push in place the three bearings



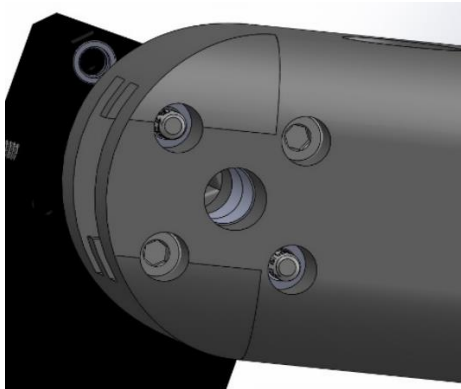
4.ROBOT ARM



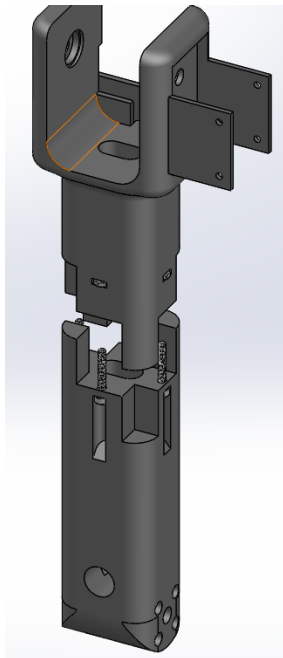
- Push in place the 2 sets screw hub in inferior segment 1 and in segment 2



- Bolt the hub together



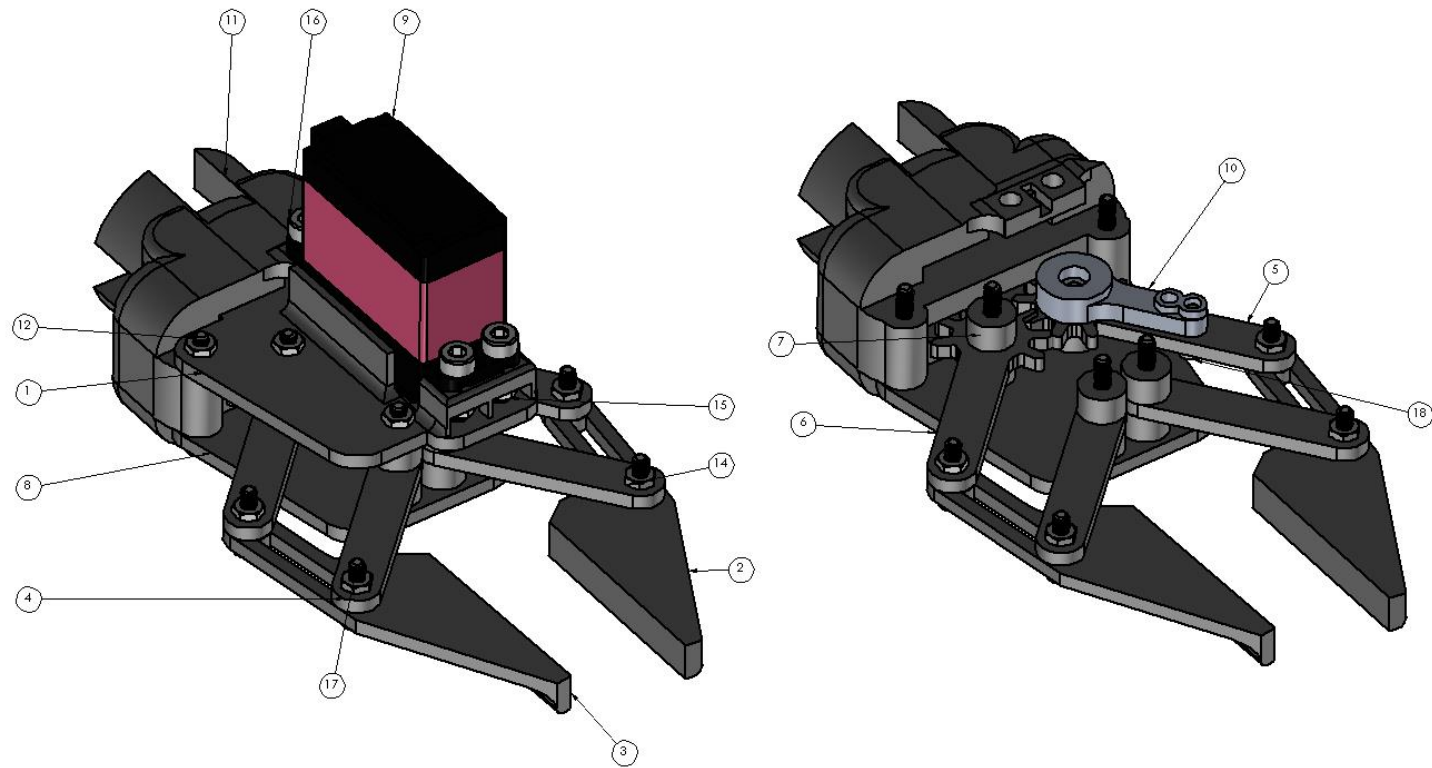
- Bolt inferior segment 1 with superior segment 1



- Fix the two shafts in their motor coupler and pass it through the robot base/superior segment 1 and the set screw hub
- Tighten each screw of the hub onto the flat surface of the shaft
- Fix each motor on both walls

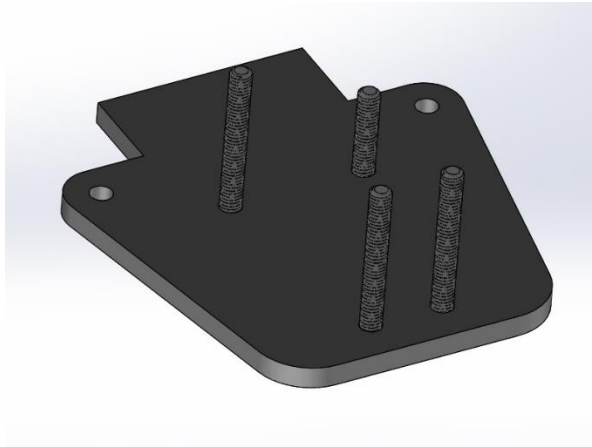


5.GRIPPER

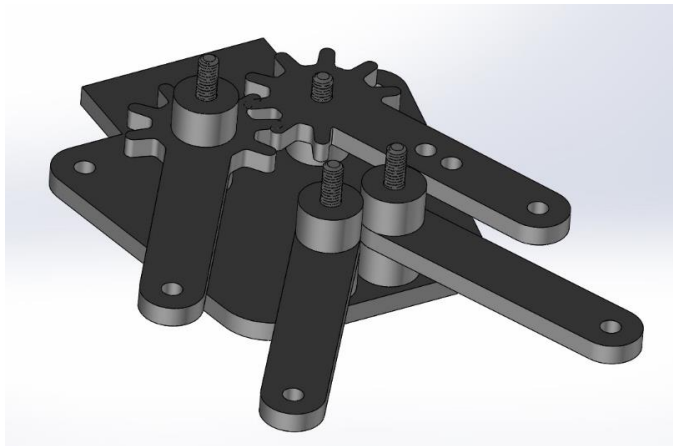


No. ARTICULO	NUMERO DE PIECE	QTE
1	superior_gripper_plate	1
2	left_gripper_tip	1
3	right_gripper_tip	1
4	front_segment	2
5	servo_gear_segment	1
6	driven_gear_segment	1
7	spacer	7
8	inferior_gripper_plate	1
9	DS3218MG.stp	1
10	servo_motor_coupler	1
11	gripper_arm_coupler	1
12	91292A123	5
13	91292A115	1
14	90710A030	9
15	90710A035	4
16	91292A118	4
17	91292A114	4
18	91292A112	1

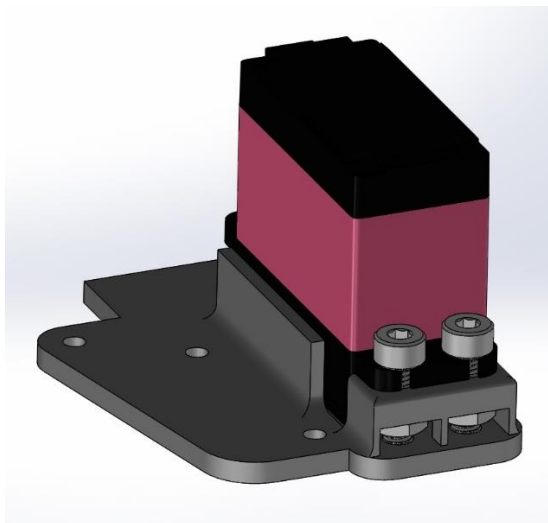
- Put these 4 bolts in the inferior gripper plate



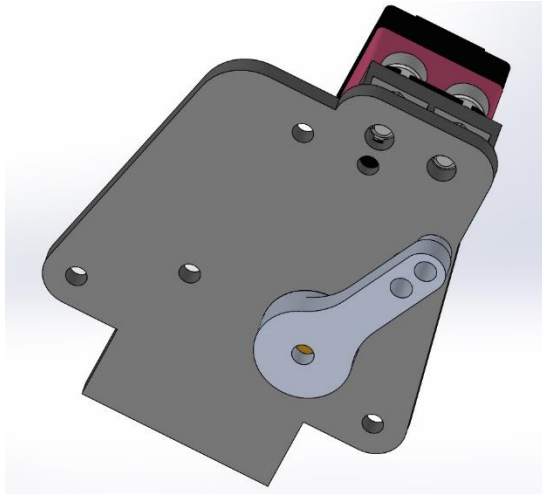
- Put in place the spacer, the gear segments, and the front segments



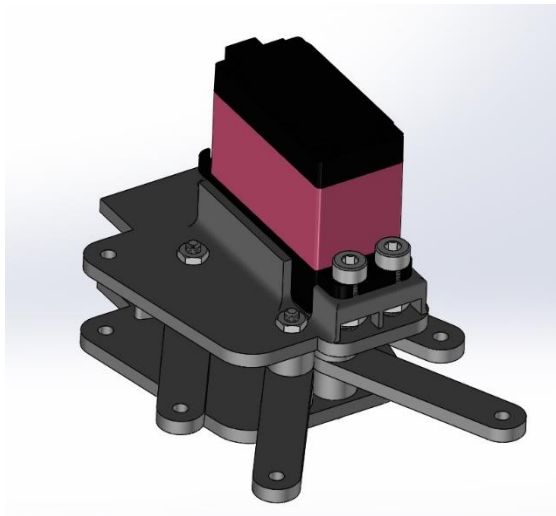
- Fix the servomotor into the superior gripper plate



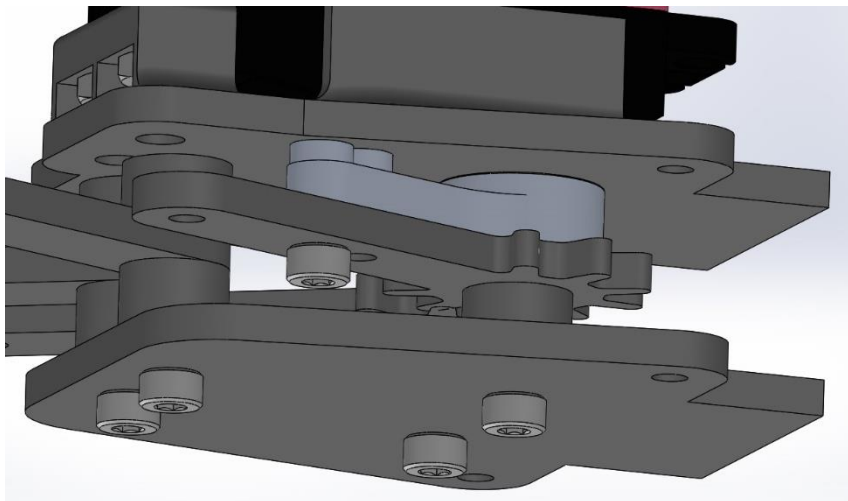
- Fix the servomotor coupler on the motor shaft



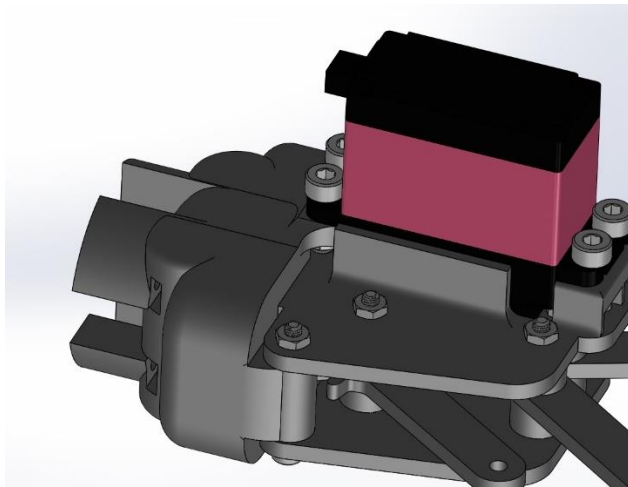
- Put the superior gripper plate on top and bolt it (not too tight)



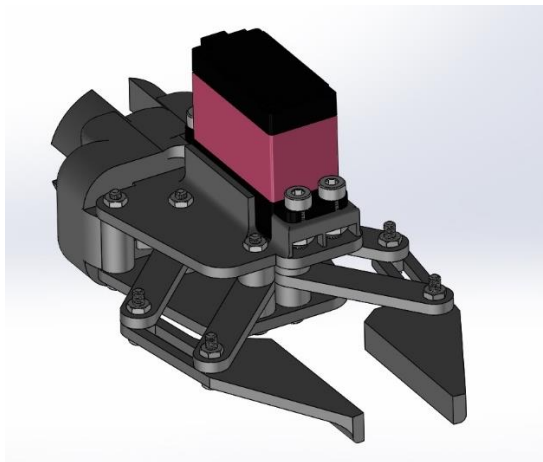
- Fix the servo gear segment into the servomotor coupler



- Push the two gripper plates into the arm coupler, bolt the plates to the arm coupler, and bolt the motor with the arm coupler

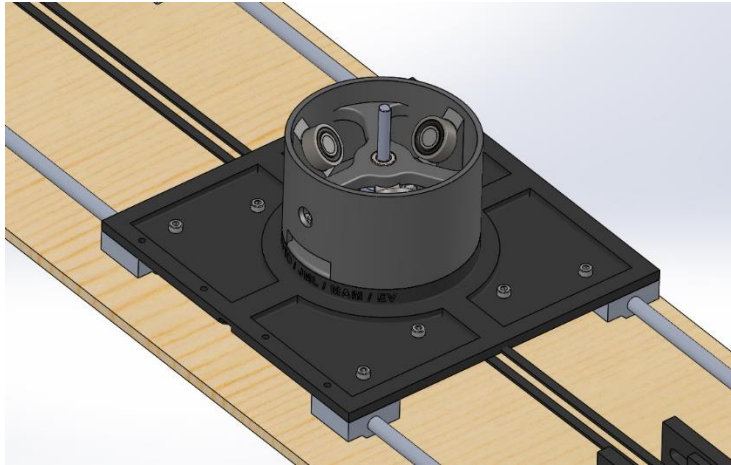


- Fix the two gripper tips

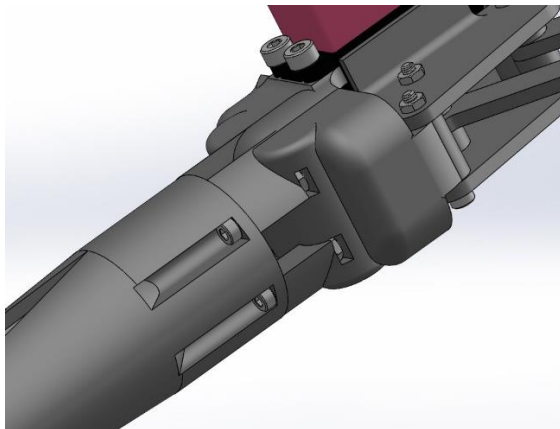


6. FINAL ASSEMBLY

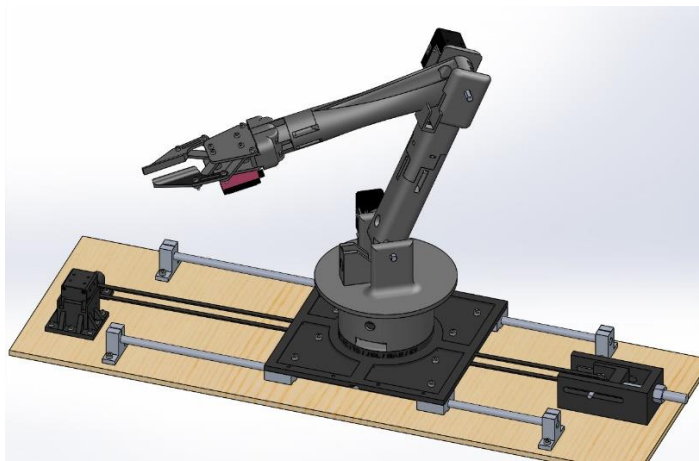
- Place the base robot plate on the linear bearing and bolt the bearing and the timing belt coupler with the plate



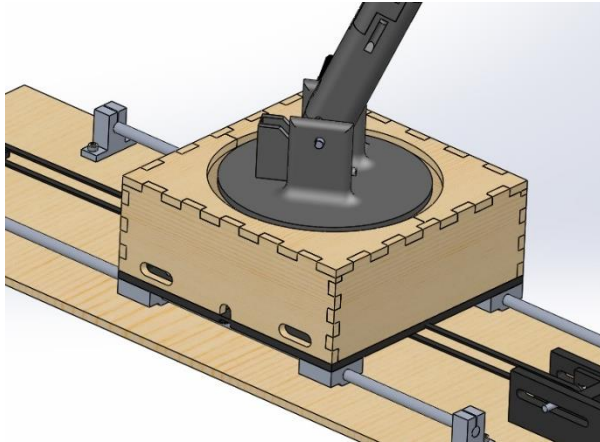
- Bolt the gripper arm coupler with segment 2



- Place the arm base on the three bearings



- Place the box on the robot base plate



- Place a nut onto the flat surface of the shaft and tighten the bolt into it

