

## Session 11

I set aside the blueooth model for now, because After linking all the components of the robotic arm, a few complications became apparent. The arm is not very stable, the 2nd servomotors supports a lot of weight due to the fact of the 3 other parts that it must move so I reprinted the part by resuiding the filling to lighten the structure and fixed all the axes of rotation to the rudder with screw and glue. I put everything back together with the pliers then connected the power supply to see if the servomotor is able to lift the whole arm with the pliers, it works.

Then in order to power all the servos, connecting them all to a breadboard and then to the arduino makes a lot of non-optimal wires, so we will use a PCA9685 servomotor driver, given that the Robotic Arm is ideally a series of motors in coordinating together, we can theoretically attach several motors that can be all powered by the Arduino.

Having taken the nvidia card from (guillaume) I tried on my side to communicate the nvidia with the arduino.