Session 7

The fully modeled forearm I launch the impressions and recover the base and the hip which must now be assembled, by grouping the parts I realized that the servomotors presented a relief at the level of the location to aim that I had not taken into account during the modeling, indeed when screwing my motor was not leaning against the support directly, the enhancement push the motor back by 3 mm which caused friction between the arm and the hip in front.

I therefore filed the part until the motor was perfectly linked to the support.

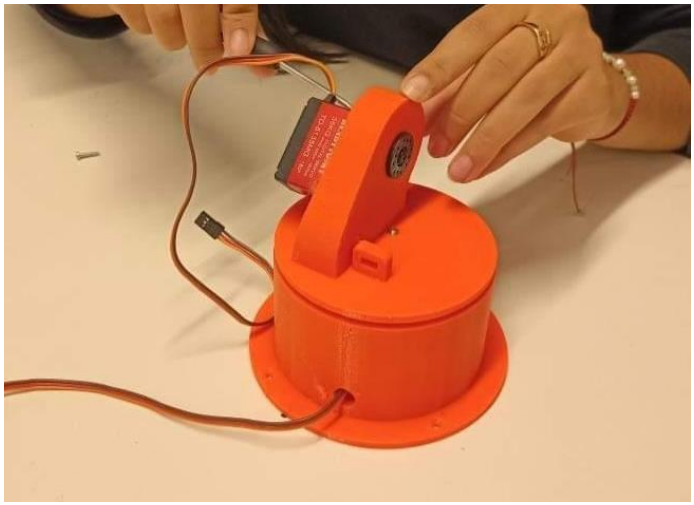

Fig 1 : assembled part

In the meantime, I launched the printing of the three component parts at the bottom.

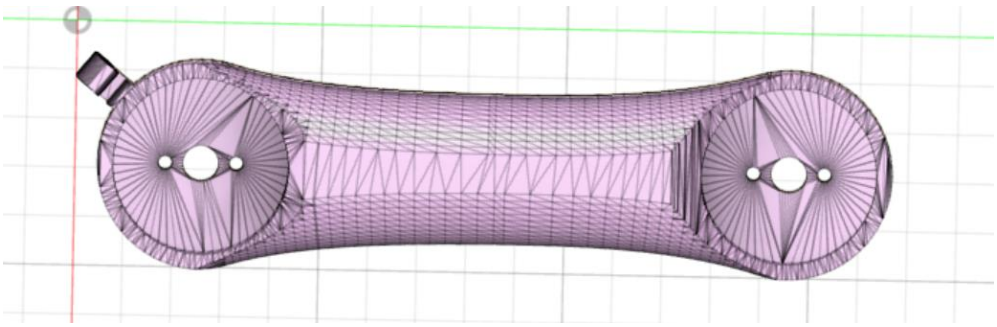

Fig 2: Arm

For fear that the piece will come off due to movement, I added a clip system at the bottom which will be attached to the waist with an elastic.

the servomotors will be controlled by a potentiometer at first and then by Bluetooth when the model will be complete.