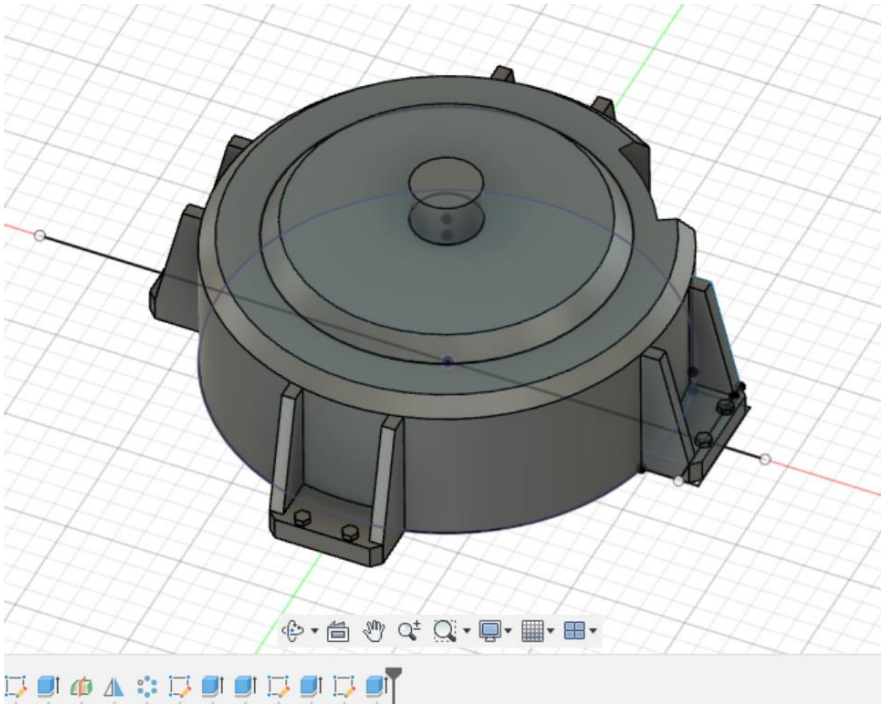
Session 3

during this session I was mainly interested in the design of the arm, which will be divided into four parts (base, jaw1 ...) capable of moving in a movement of two to three axes, an articulated arm at a scale capable of doing a translational movement was possible but we still choose to start on a gear



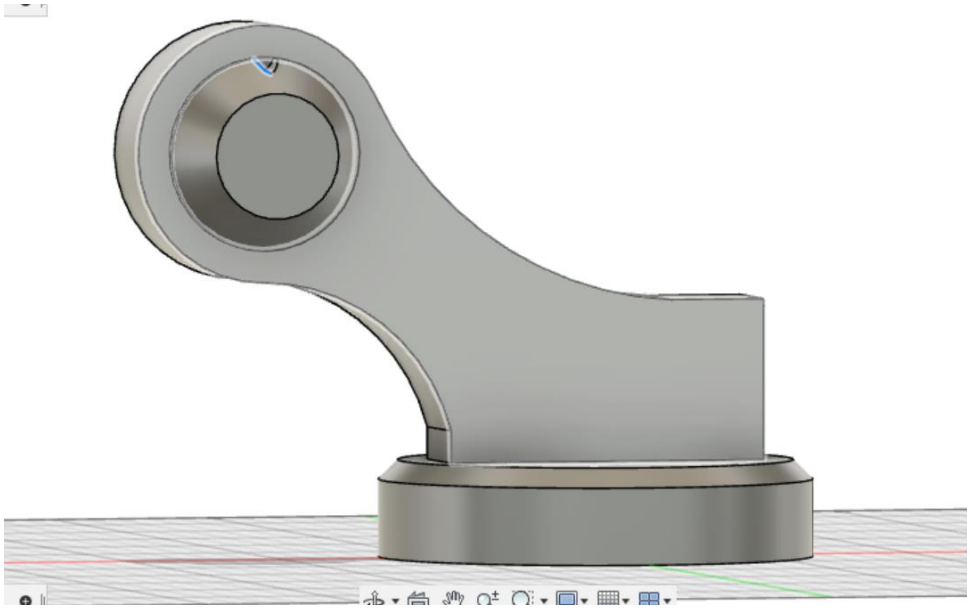
Base of the arm

Details of construction:

the base is extruded by 7cm and is 20cm wide (the space needed to put 2 servomotors; the bottom of the base is drilled to allow the card-motor connection. a circular network of 4 mounting brackets allows the base to be attached to the bodywork,180° rotation is possible.

the base is overhung by a peak of 2cm where the jaw 1 will be installed (connection between the base and the first axis of rotation).

the gear is nevertheless being modeled, to avoid breaking too many servomotors, I'm trying to figure out if putting all the motors down near the case is better with calculus.



Jaw 1 (first sketch)