Session 4 :

During this session I continued to work on the robotic arm, to prevent the jaw 1 servo from being subjected to all the force necessary to lift the arm, I added a 10-tooth gear to transmit the movement.

The first servomotor will be aimed below the base of the robot allowing chassis/robot communication; the second is now attached to the back of the jaw1.

then I started modeling the jaw2 (still in progress) which allows us to see the real evolution of the arm, we imagine an arm 25 cm high made of targeted parts, solid and stable to have the strength to open a door.

the first 3D impressions will be launched during this week.

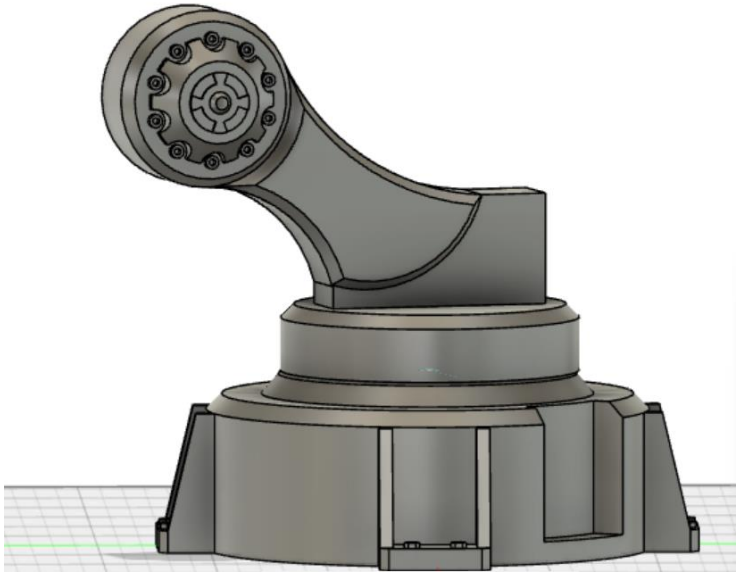

Fig1: Base-jaw1 connection

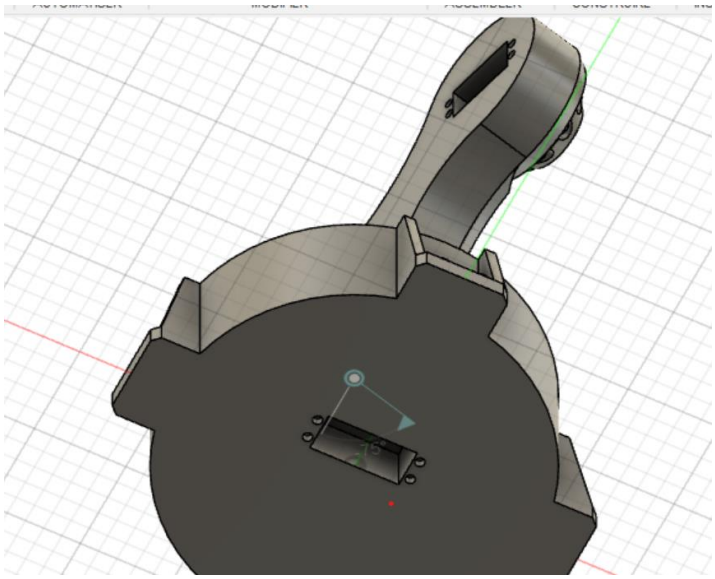

Fig2: The 2 servomotors

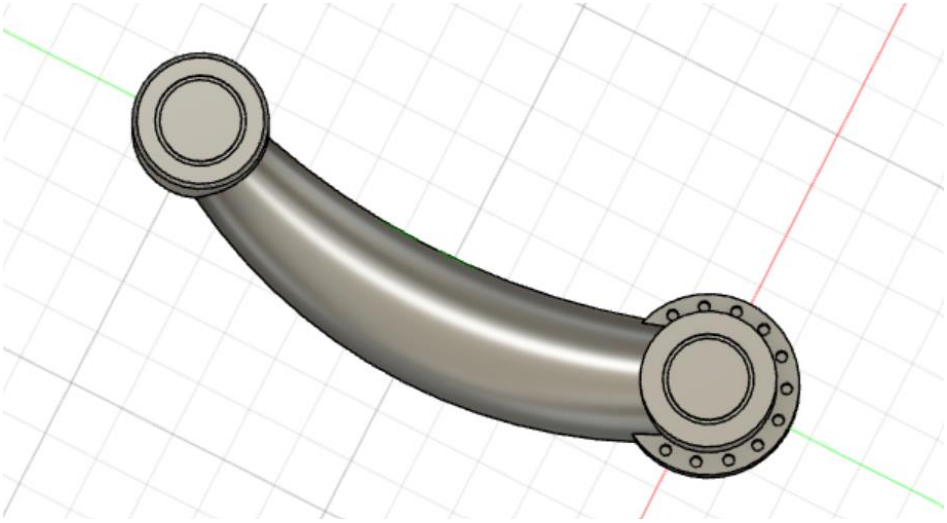

Fig3: jaw 2 where the clamp will go up (still in progress).

Actually, I’m still thinking about the shape of the clamp.

All modeling STL files will be uploaded to Github.