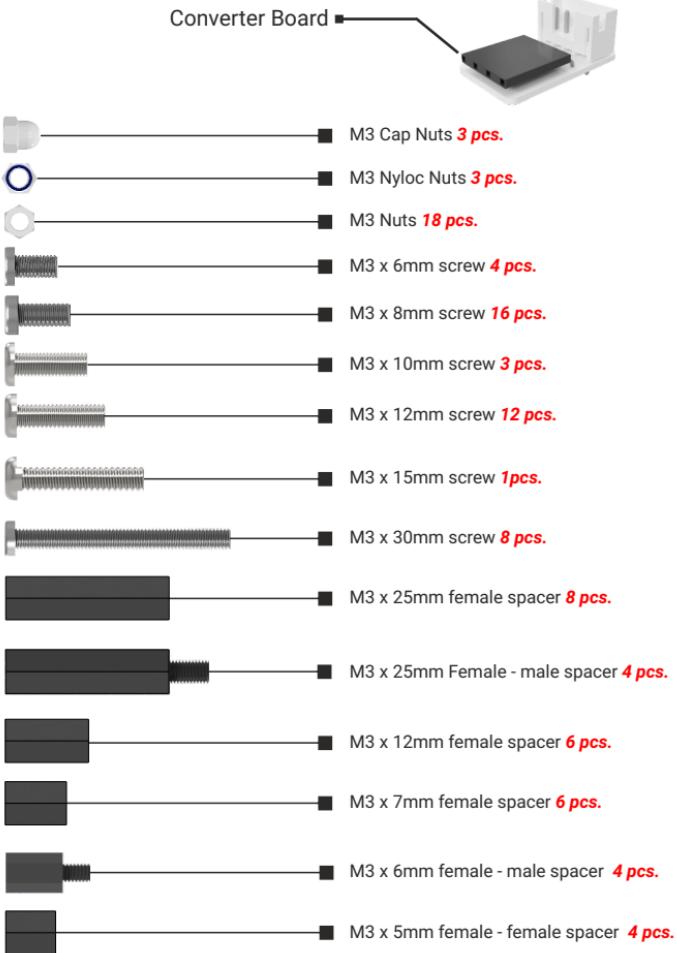
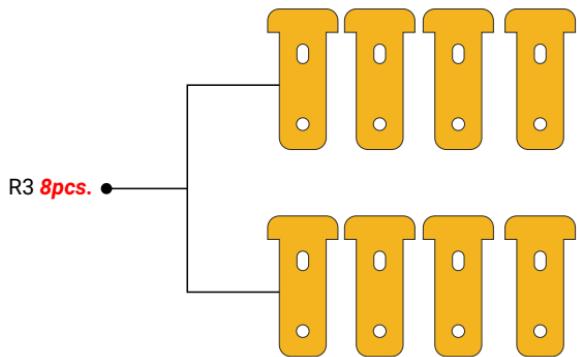




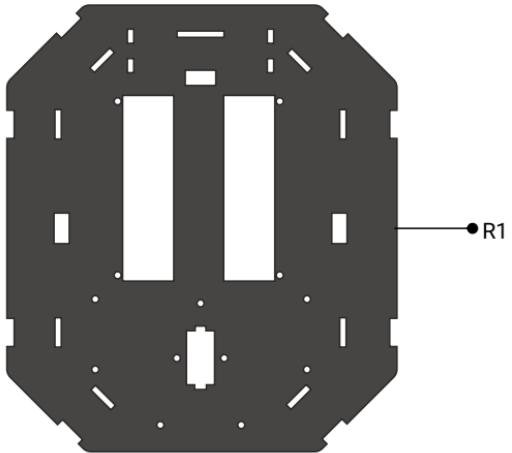
## Required Components to build TrackerBot



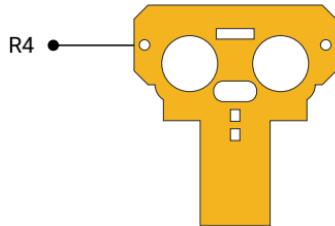
## Required Parts



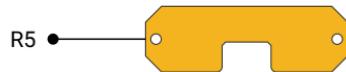
R3 **8pcs.**



R1



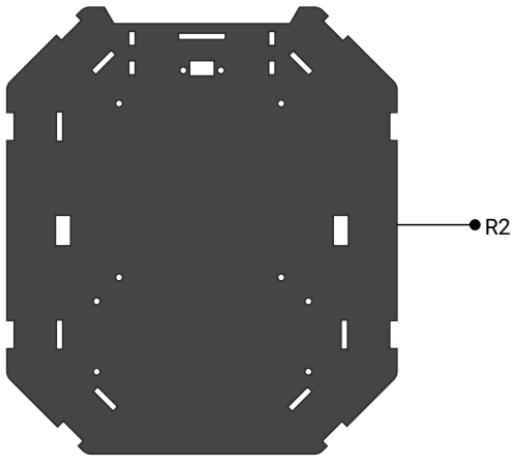
R4



R5

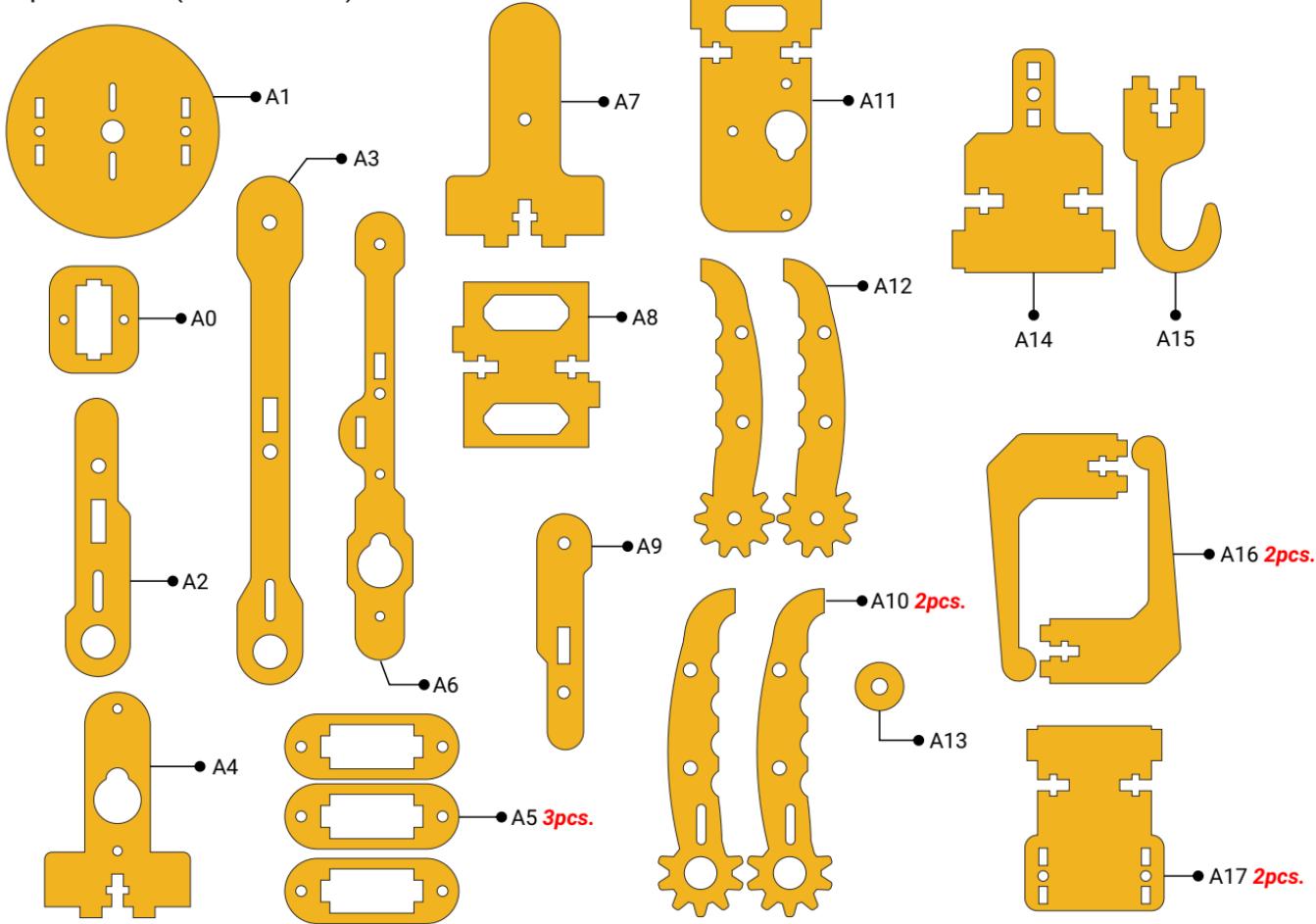


R6



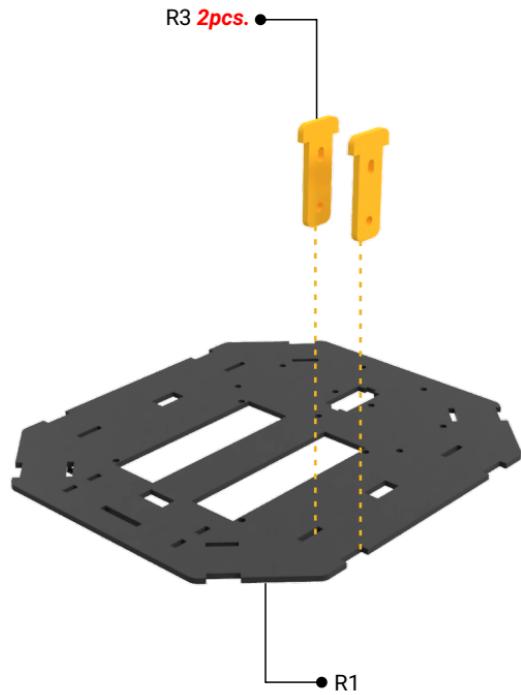
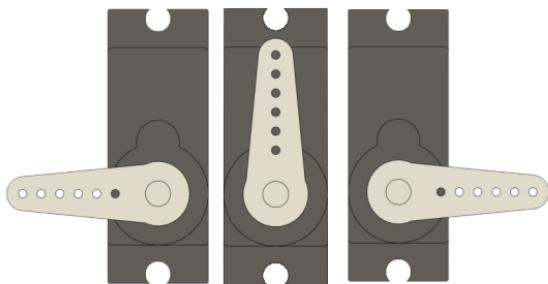
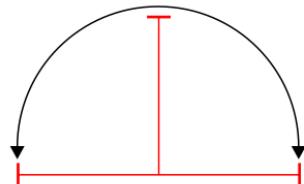
R2

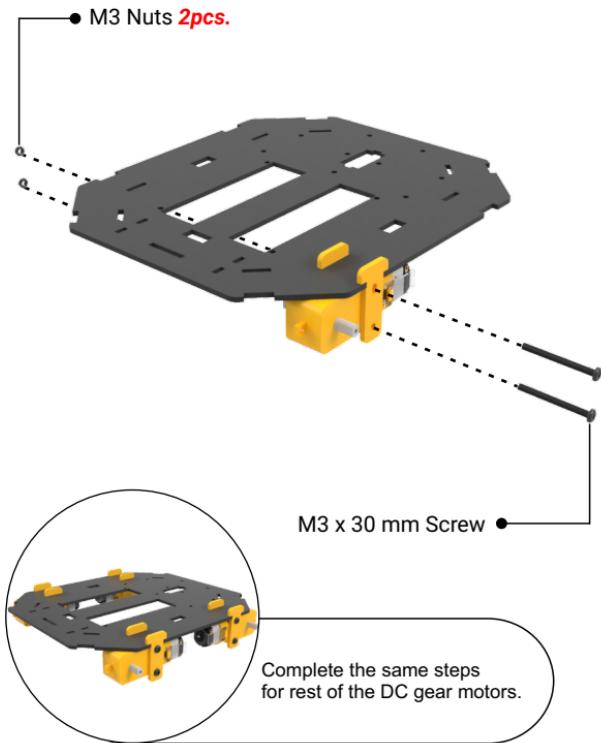
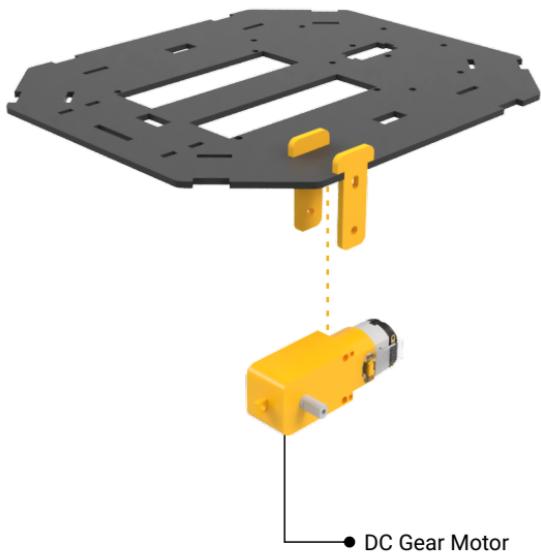
## Required Parts ( Robotic Arm )

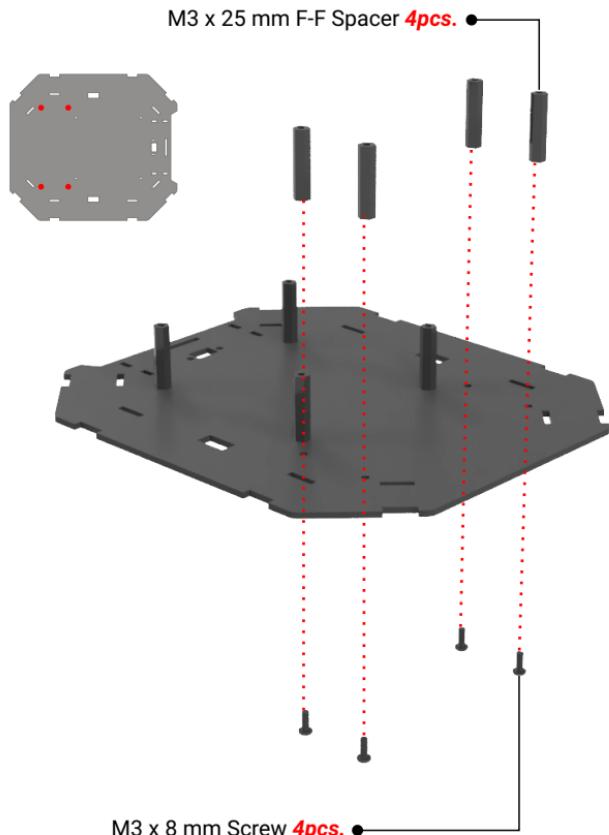
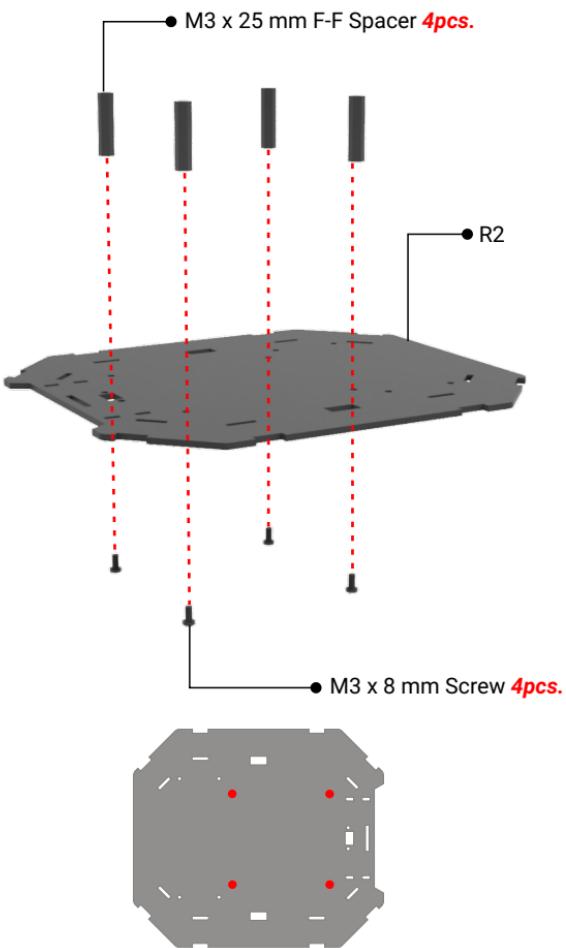


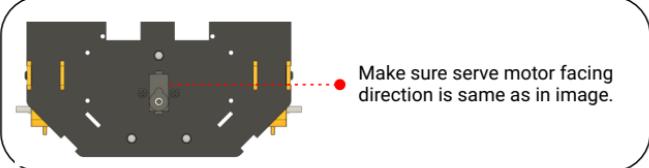
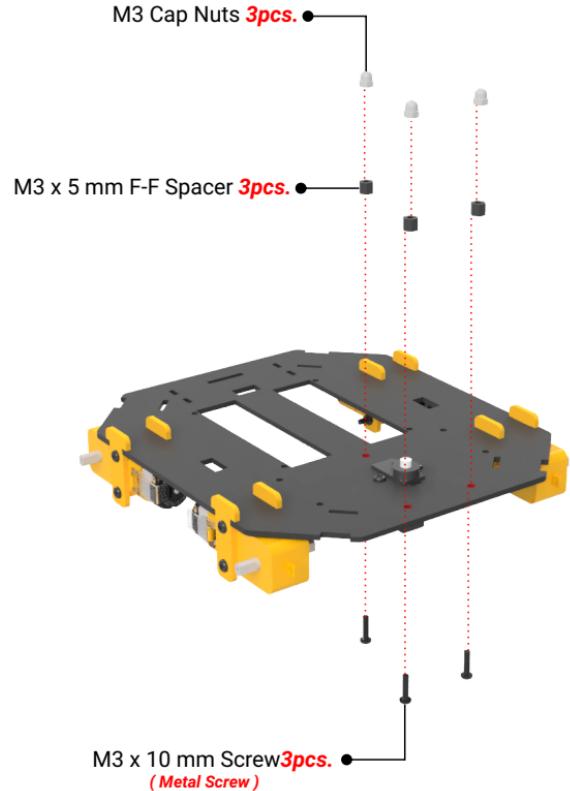
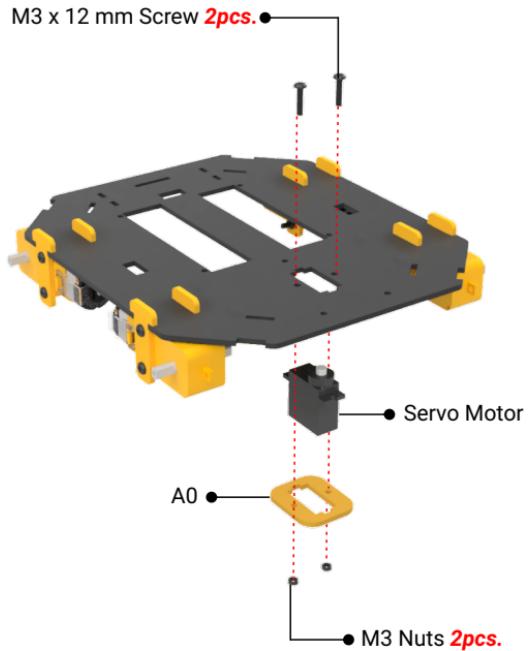
## Calibrating the Servo Motors.

To ensure that the Robotic Arm operates smoothly, it is crucial to calibrate the servo motors properly. There are various methods that can be used to achieve this, and the provided library code is just one of them. It is essential to follow the instructions provided and make sure that the servo motors are calibrated correctly, as demonstrated in the images below.

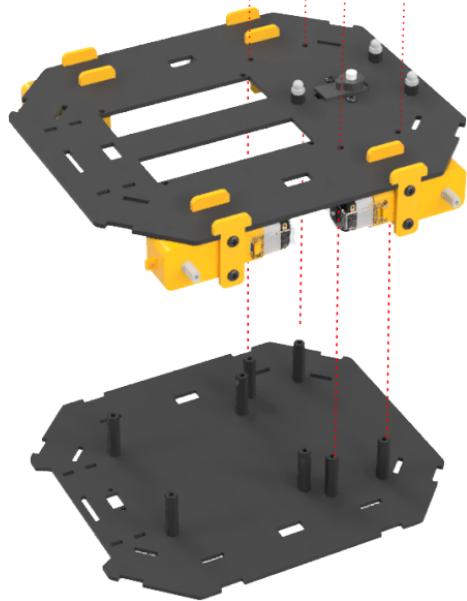




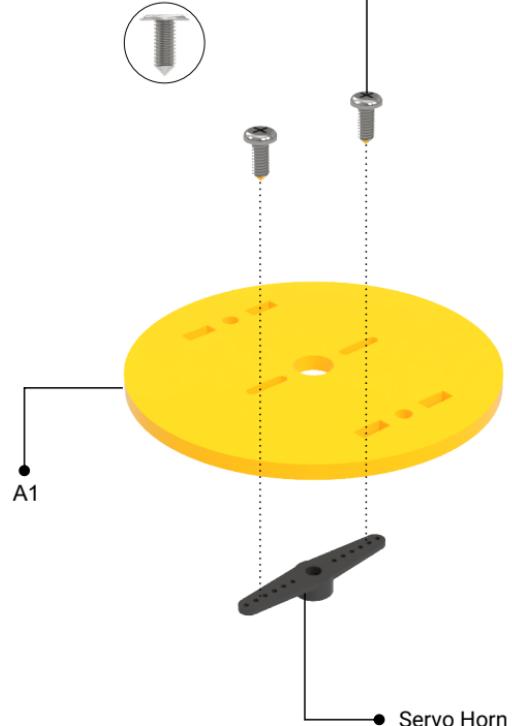


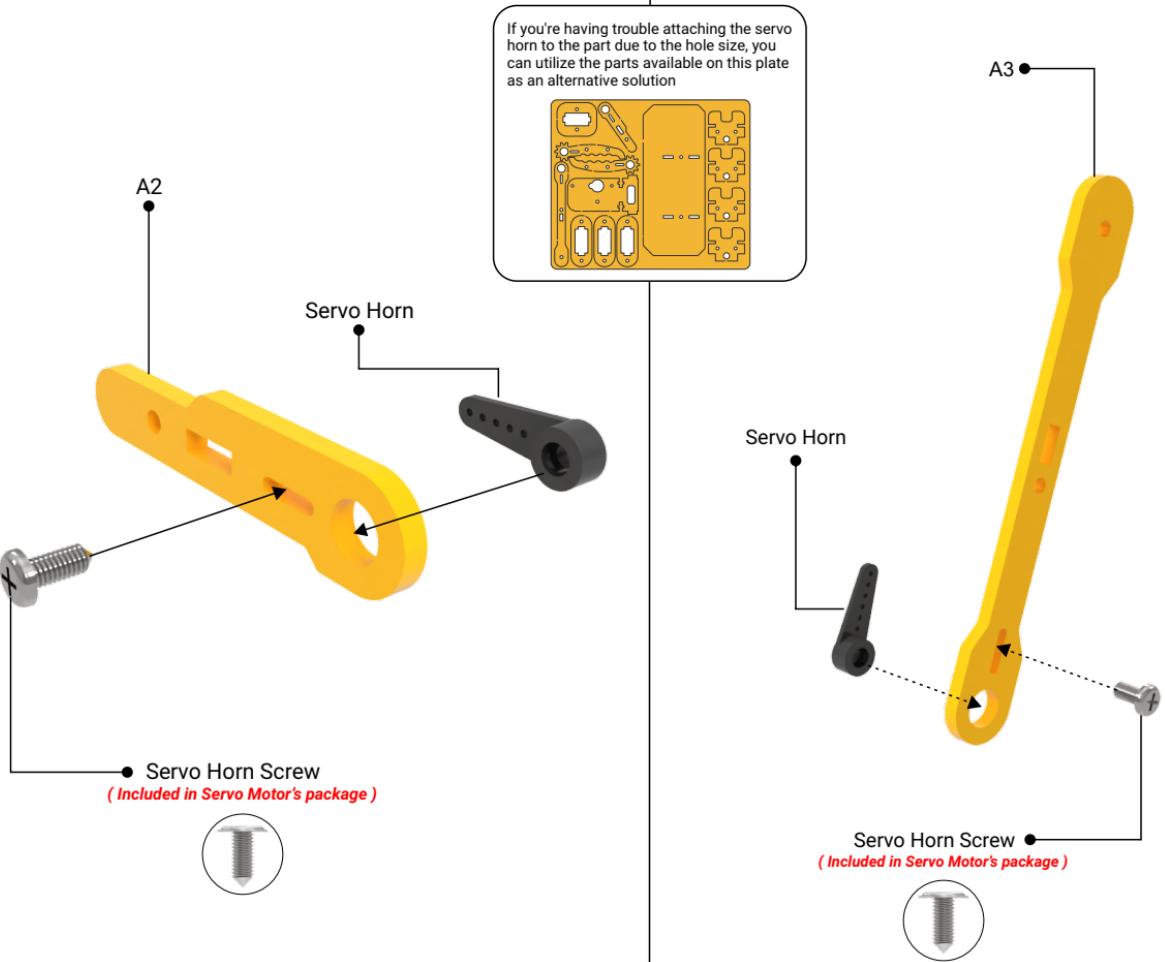


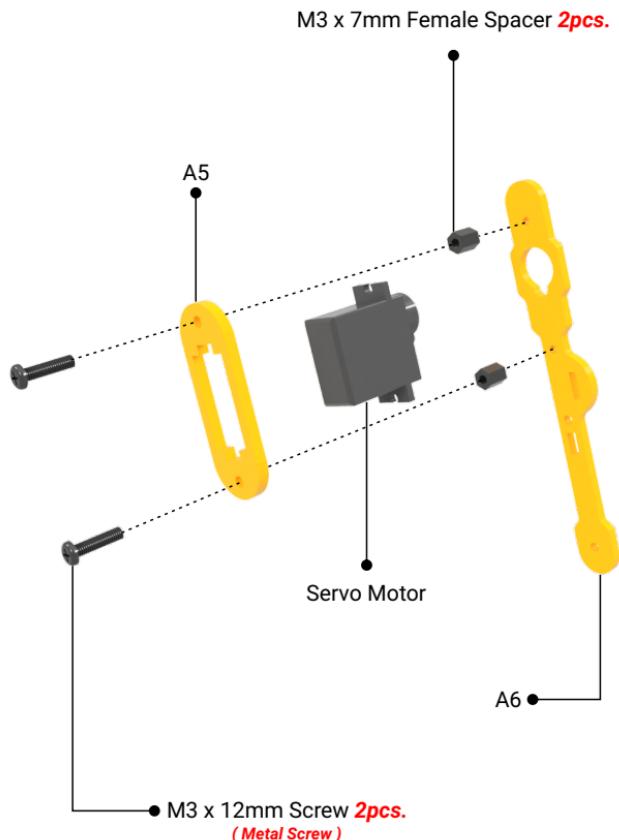
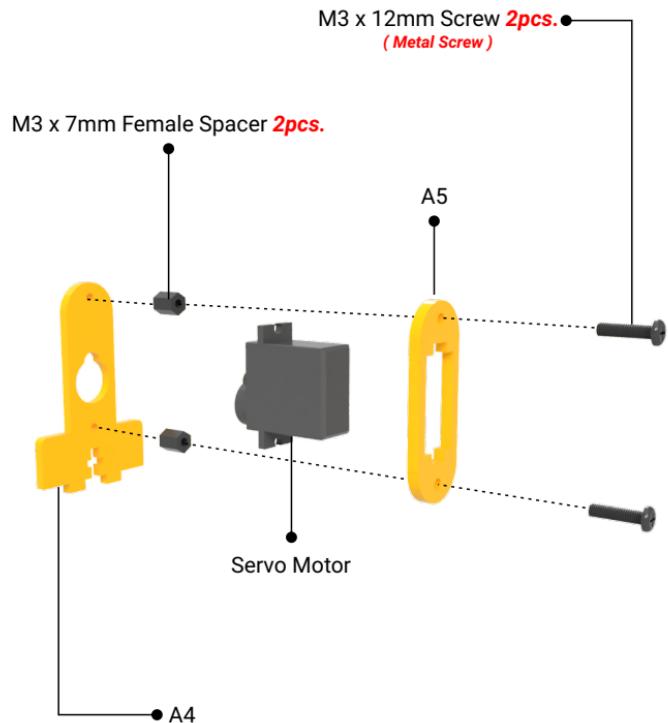
M3 x 8 mm Screw **4pcs.**

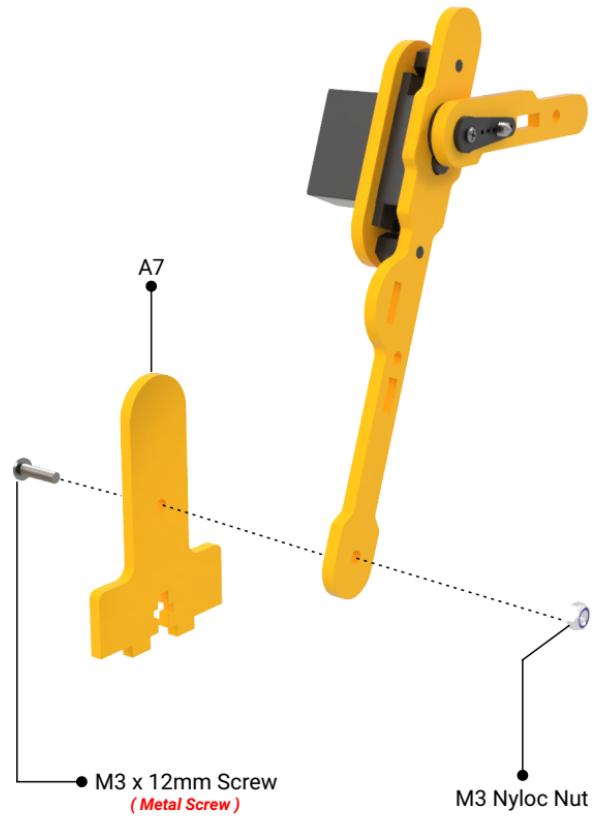


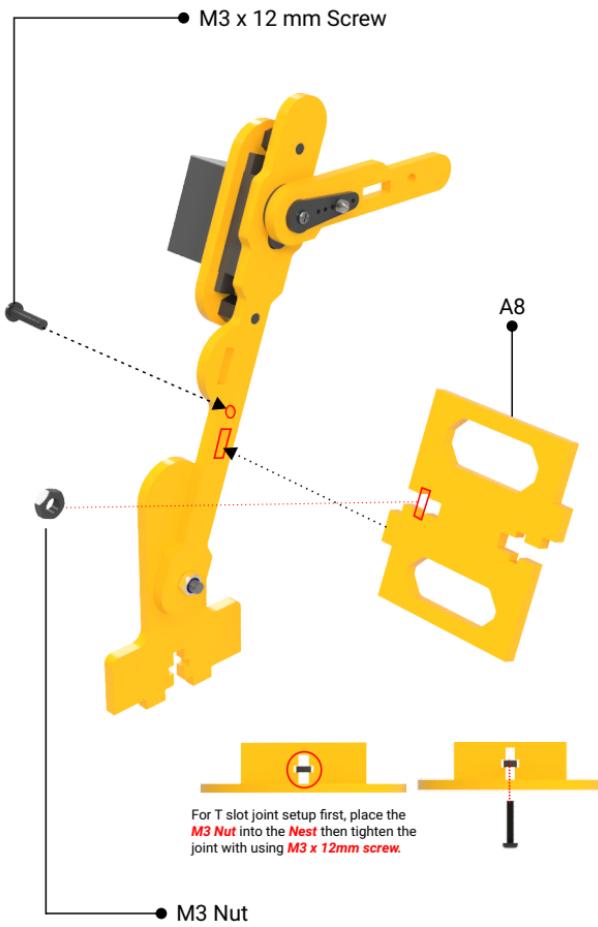
Servo Horn Screw **2pcs.**  
( Included in Servo Motor's package )





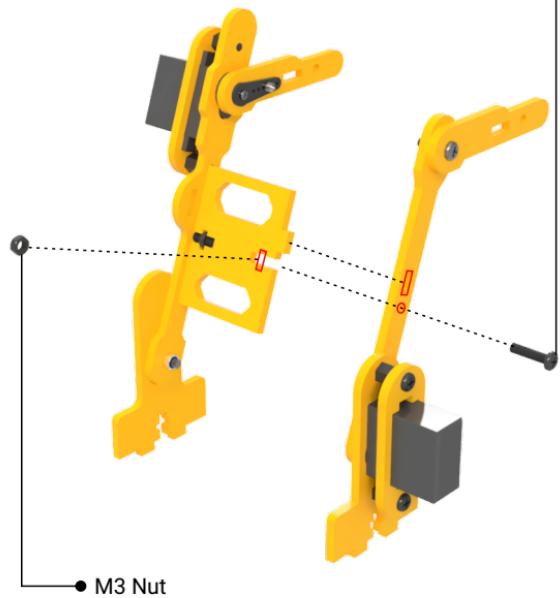




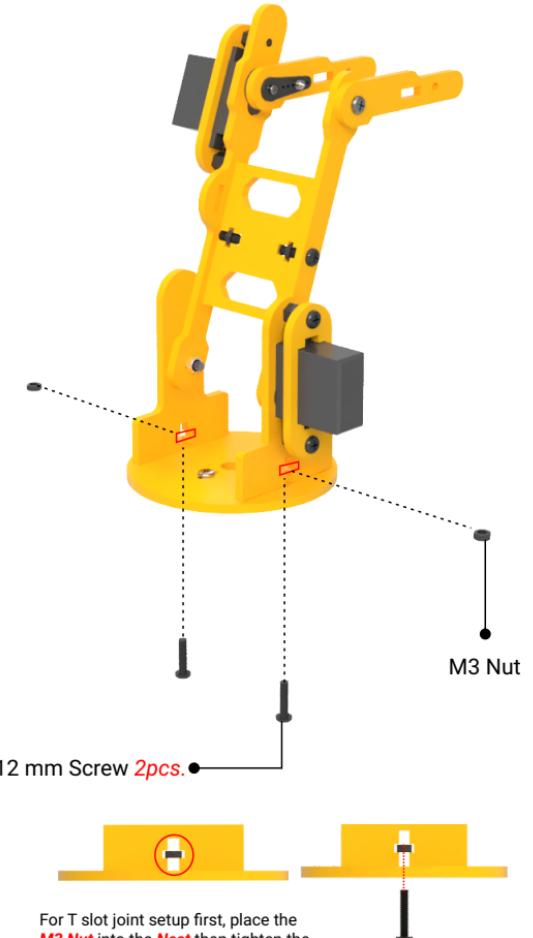
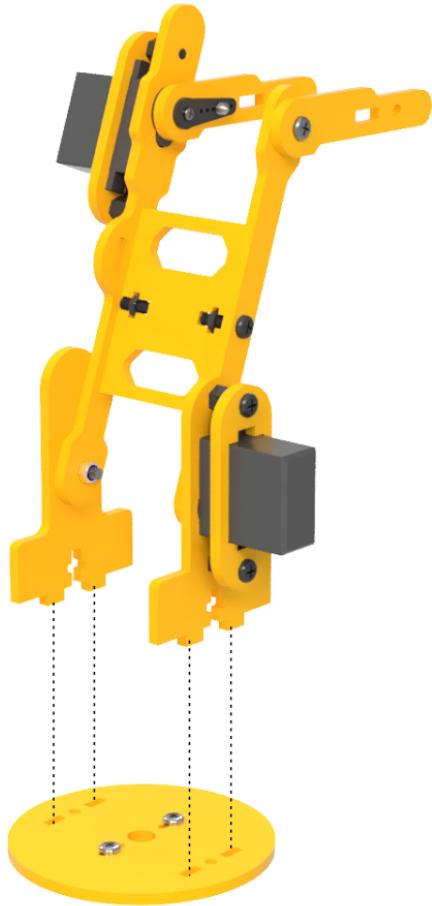




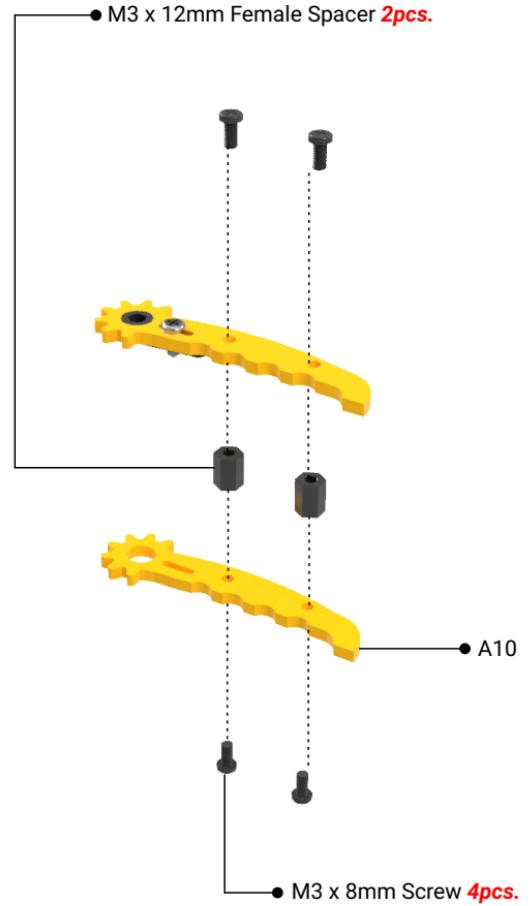
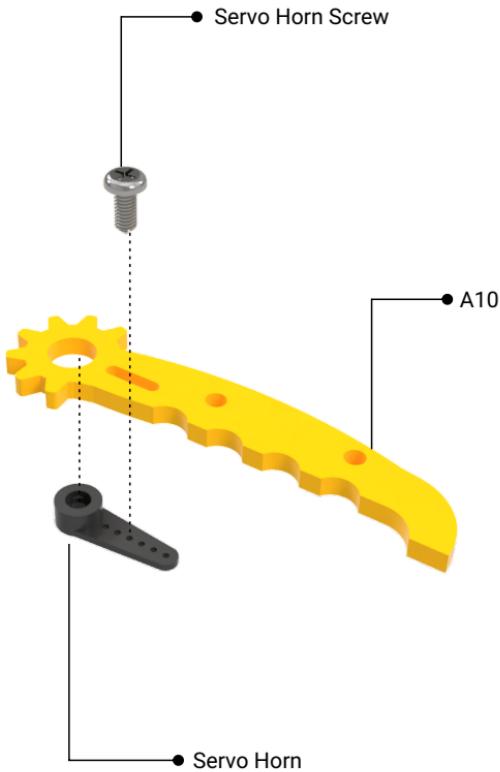
M3 x 12 mm Screw •

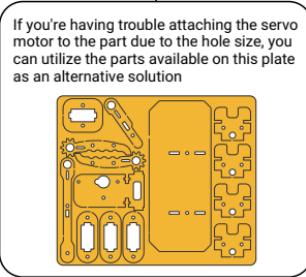
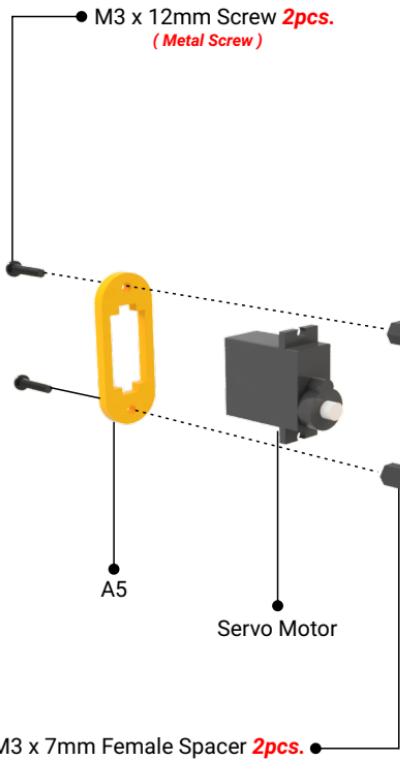


For T slot joint setup first, place the  
M3 Nut into the Nest then tighten the  
joint with using M3 x 12mm screw.



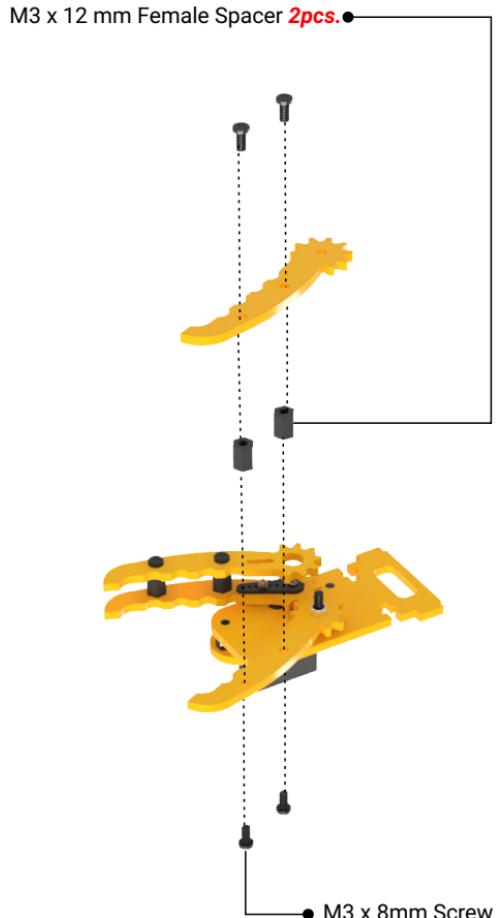
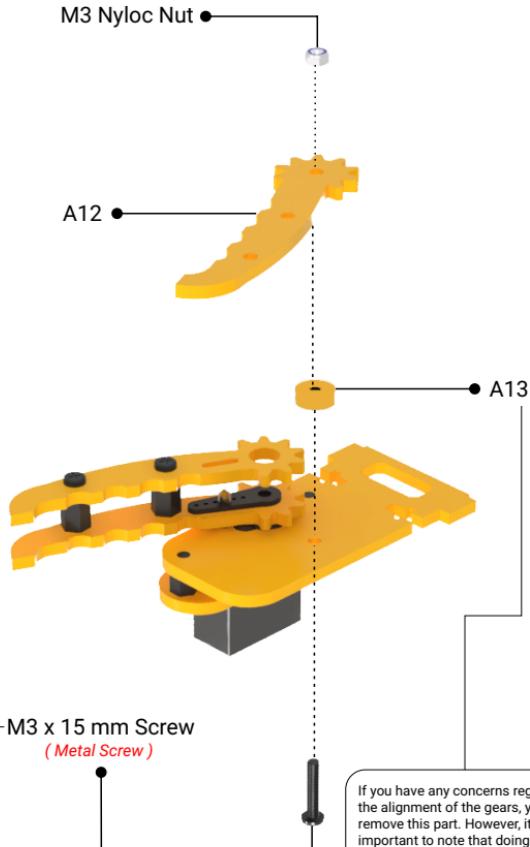
For T slot joint setup first, place the  
**M3 Nut** into the **Nest** then tighten the  
joint with using **M3 x 12mm screw**.

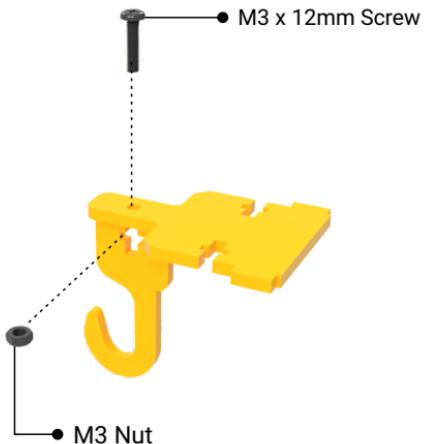
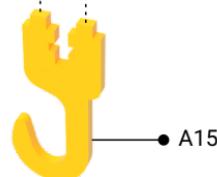
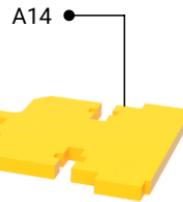
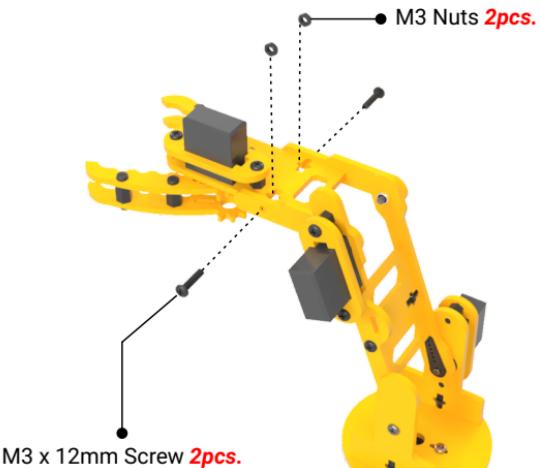
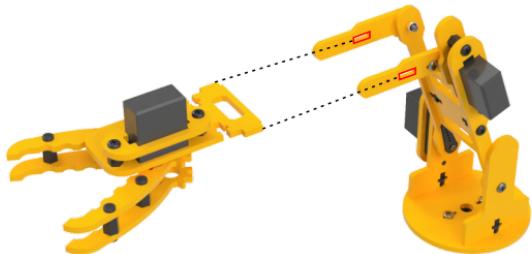


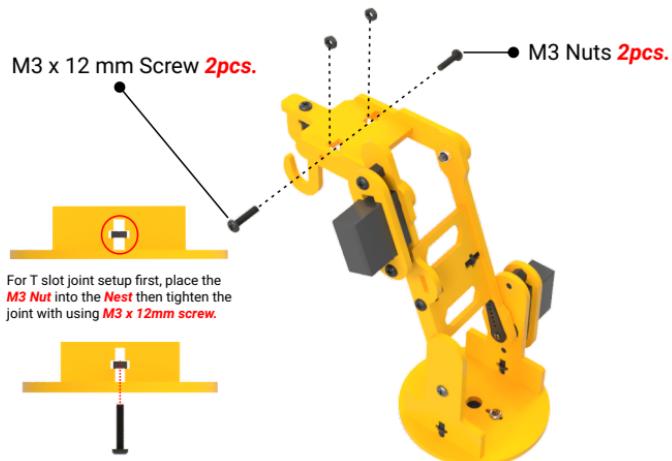
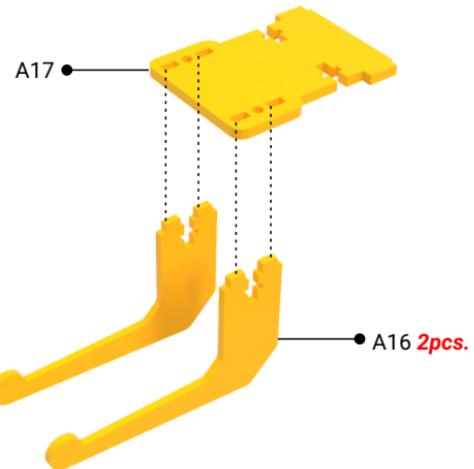


Servo Mounting Screw  
( Included in Servo Motor's package )

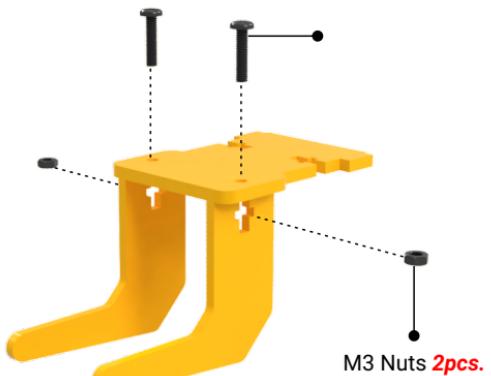


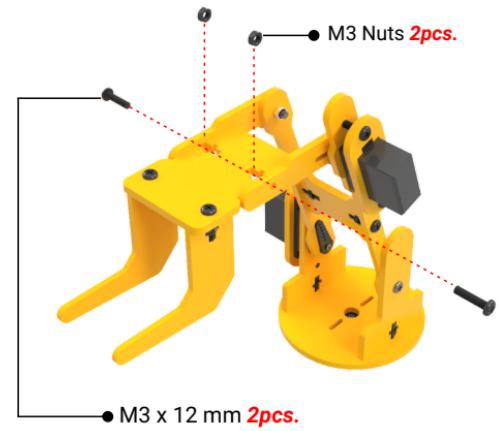
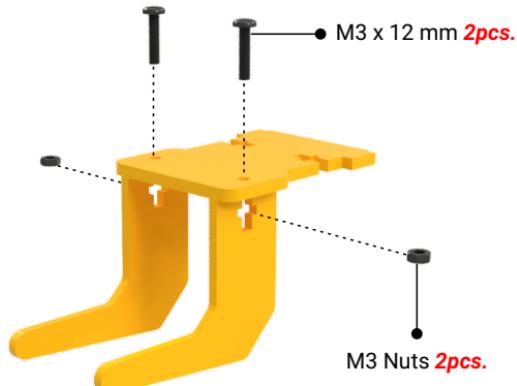
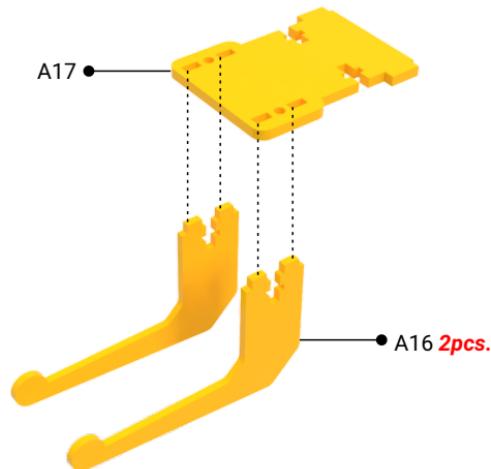


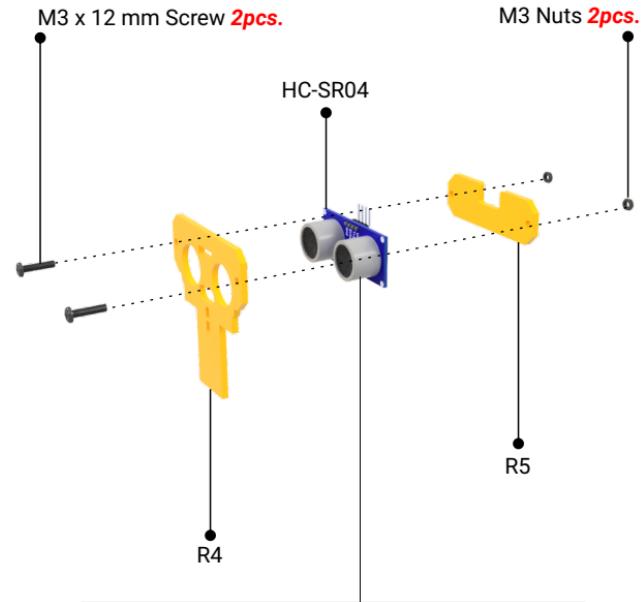
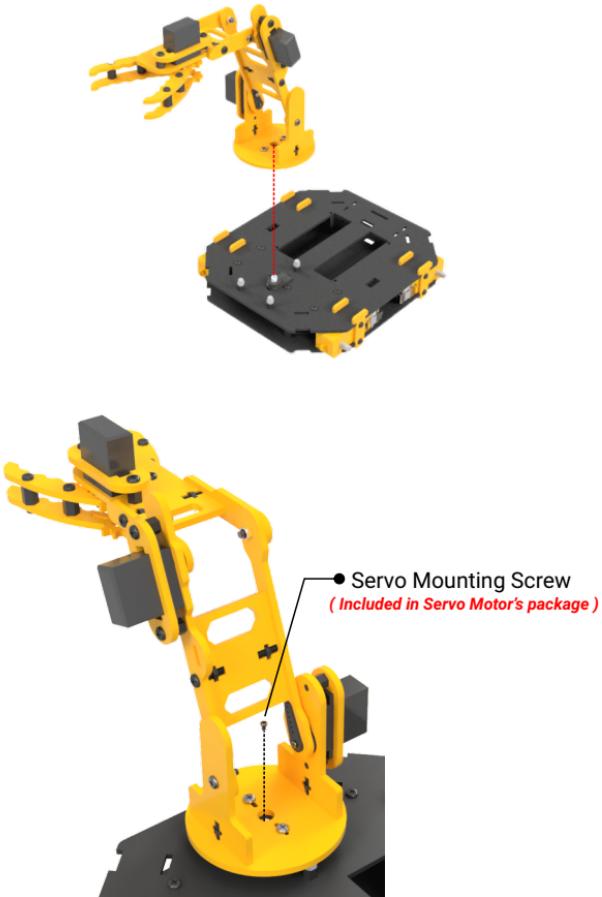




For T slot joint setup first, place the  
*M3 Nut* into the *Nest* then tighten the  
joint with using *M3 x 12mm screw*.







Make sure HC-SR04 pins are facing upward as in the image.

