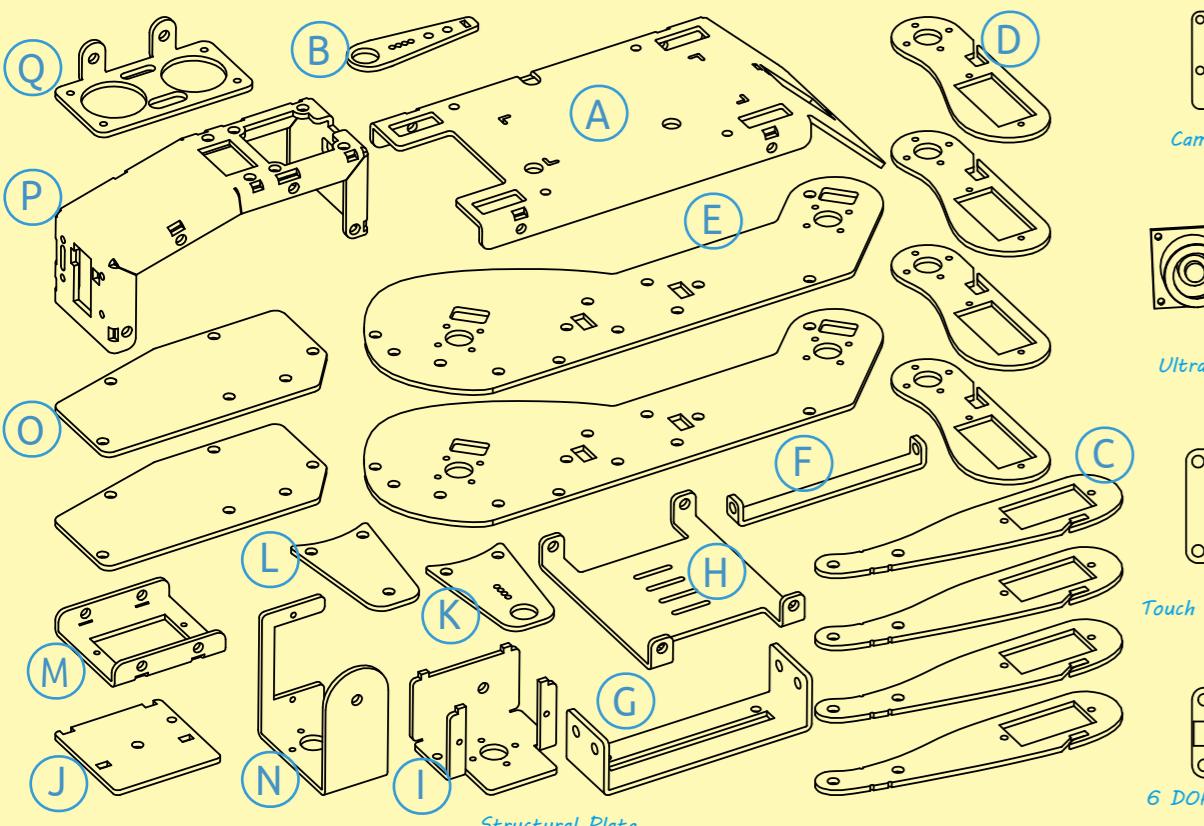


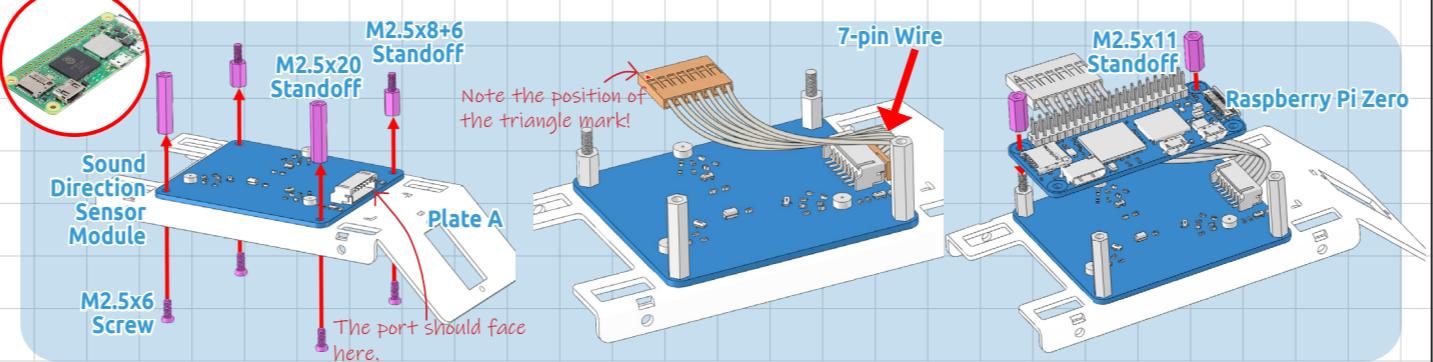
SUNFOUNDER PiDOG KIT

Get tutorial at: pidog.rtfd.io

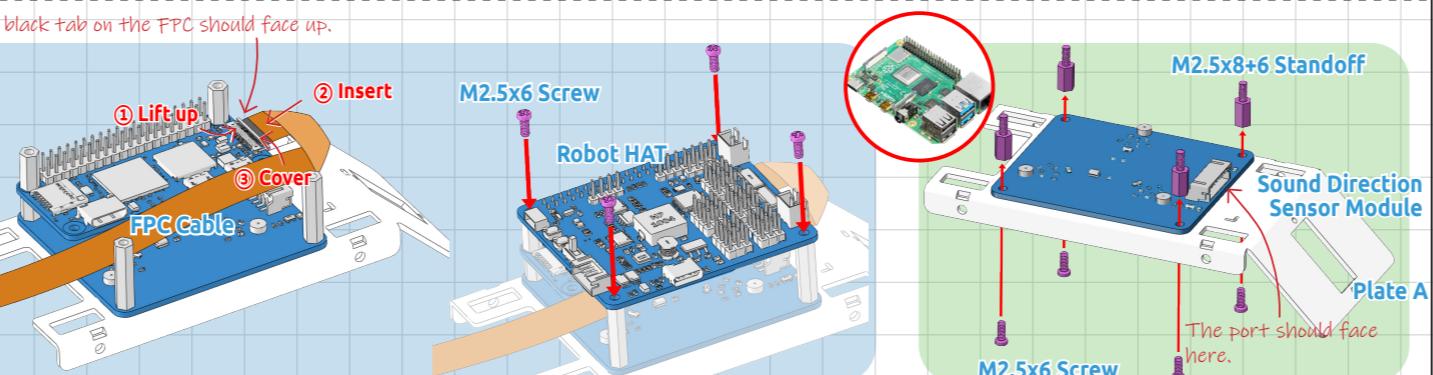


| | |
|--------------------------------------|---------------------------------|
| M1.5x3 Self-tapping Screw(46) | R2048 Rivet(6) |
| M2x4 Screw(26) | R2655 Rivet(4) |
| M2x8 Screw(6) | R3055 Rivet(34) |
| M2.5x6 Screw(12) | R3090 Rivet(10) |
| M3x6 Screw(18) | M2.5x8+6 Standoff(6) |
| M3x12 Screw(4) | M2.5x11 Standoff(6) |
| M3 Nut(4) | M2.5x20 Standoff(5) |
| Spring Washer(10) | M3x11 Copper Standoff(6) |
| Metal Washer(4) | Cable Tie(2) |
| | Cable Warp |
| | FPC / FFC |
| | 4-pin Wire |
| | 7-pin Wire |

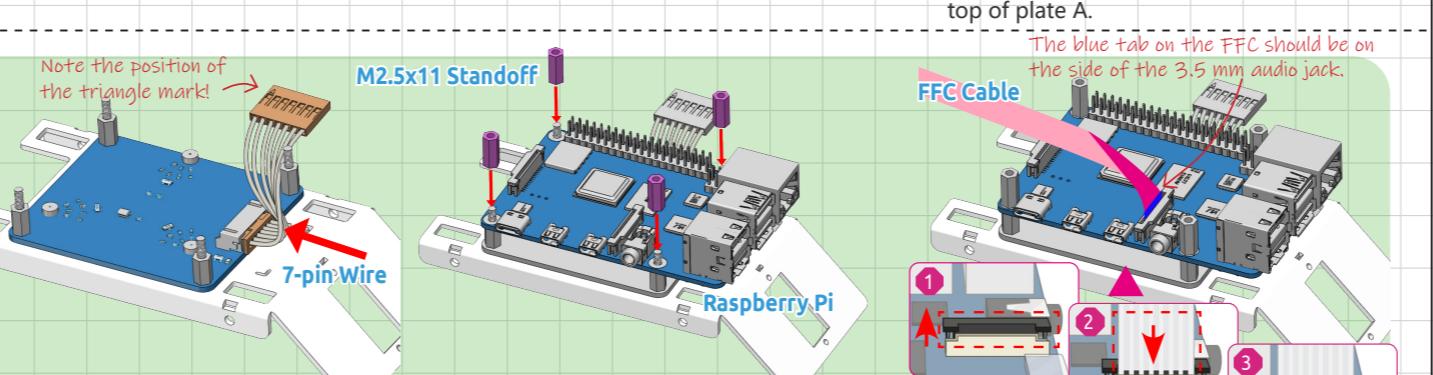
ASSEMBLE



Step 2: Insert a 7-pin wire to the module.

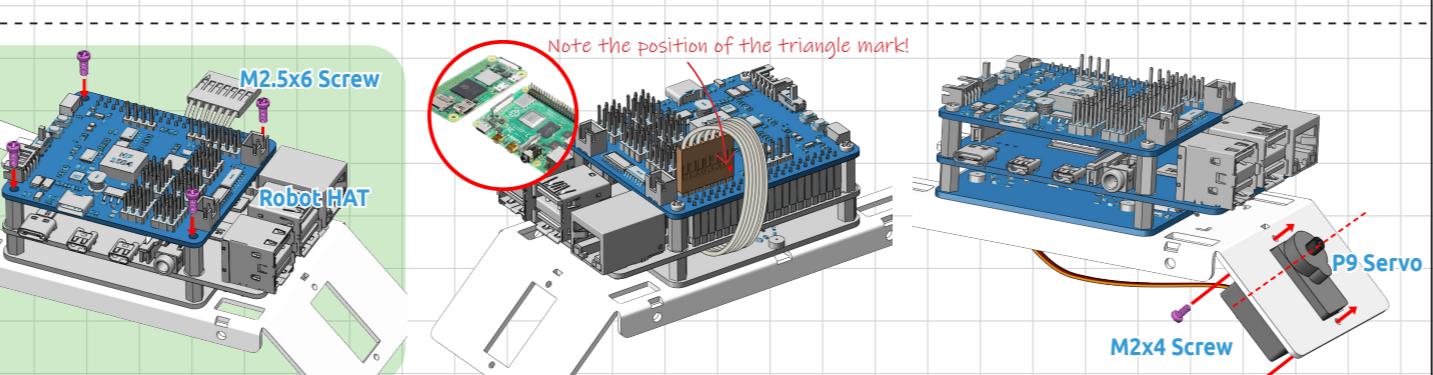


Step 4: An FPC is inserted into the Raspberry Pi to connect the camera module.



Step 2: Insert a 7-pin wire to the module.

Step 3: Attach the Raspberry Pi to the top of the sound direction sensor module.

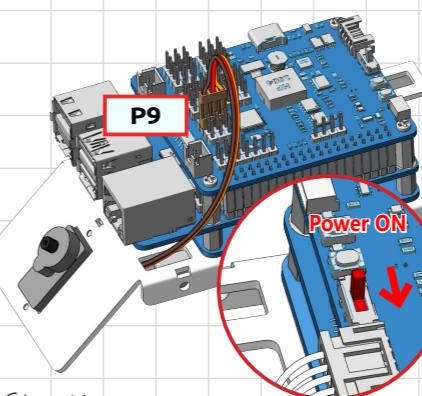


Step 5: Now insert and secure the Robot HAT.

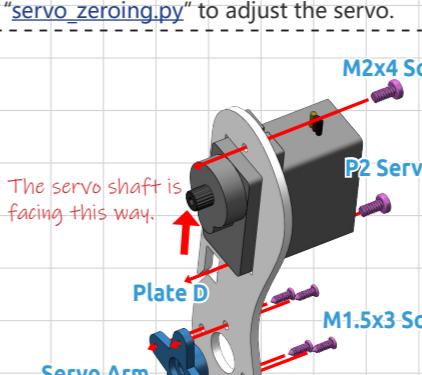
The next steps apply to both. Plug a servo to plate A. P9 should be marked on the wire connector for easy differentiation, since it's also where the servo should be connected.



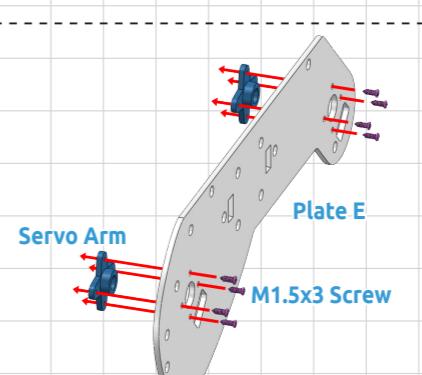
Step 7: Put a velcro on the bottom of plate A. Attach the other side of the velcro to the battery.



Step 9: The smallest screw include in the servo package.

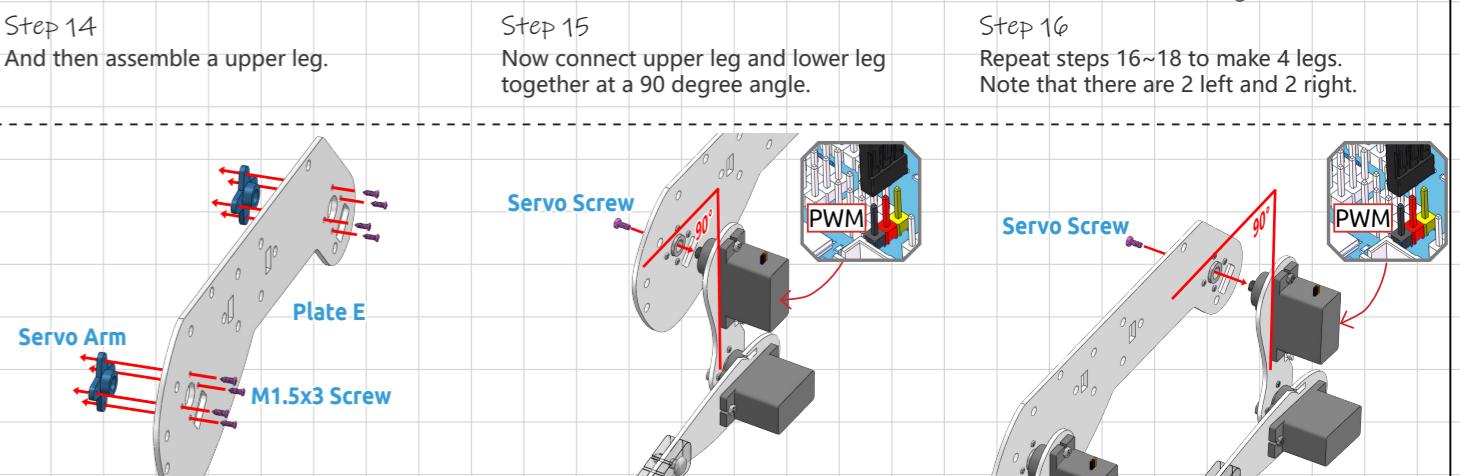


Step 11: Now to make a flexible tail for PiDog and secure it up.



Step 13: Run "servo_zeroing.py" and connect the servo to any PWM Pin for zeroing.

Step 14: And then assemble a upper leg.



Step 16: Repeat steps 16~18 to make 4 legs. Note that there are 2 left and 2 right.

Step 17: Attach two cross servo arms to plate E.

Step 18: Secure the assembled leg to plate E at a 90 degree angle.

