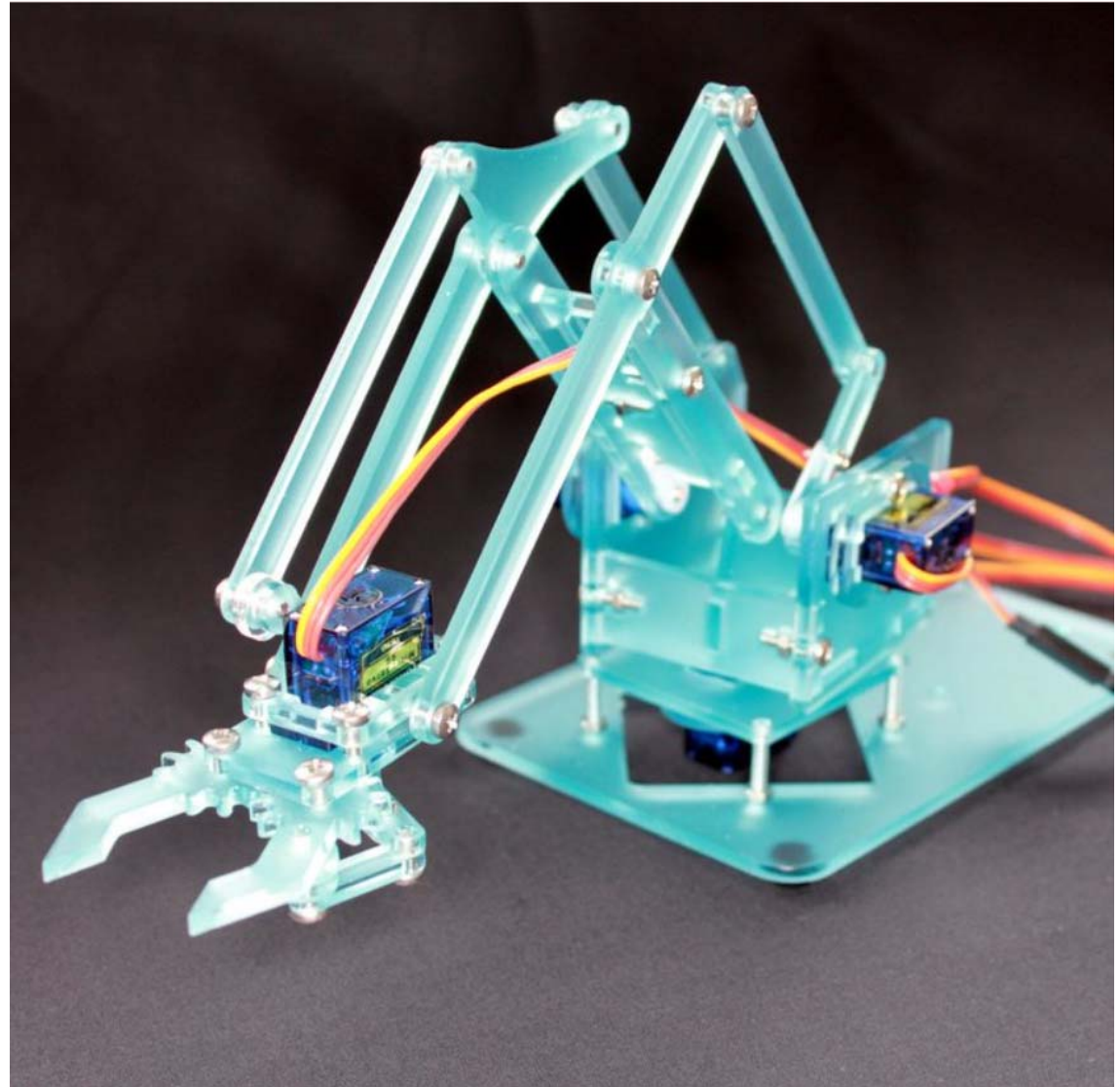


# 협업로봇팔

조립메뉴얼





## M3 볼트/너트

Nut x 10  
 6mm x 9  
 8mm x 12  
 10mm x 3  
 12mm x 7  
 20mm x 4



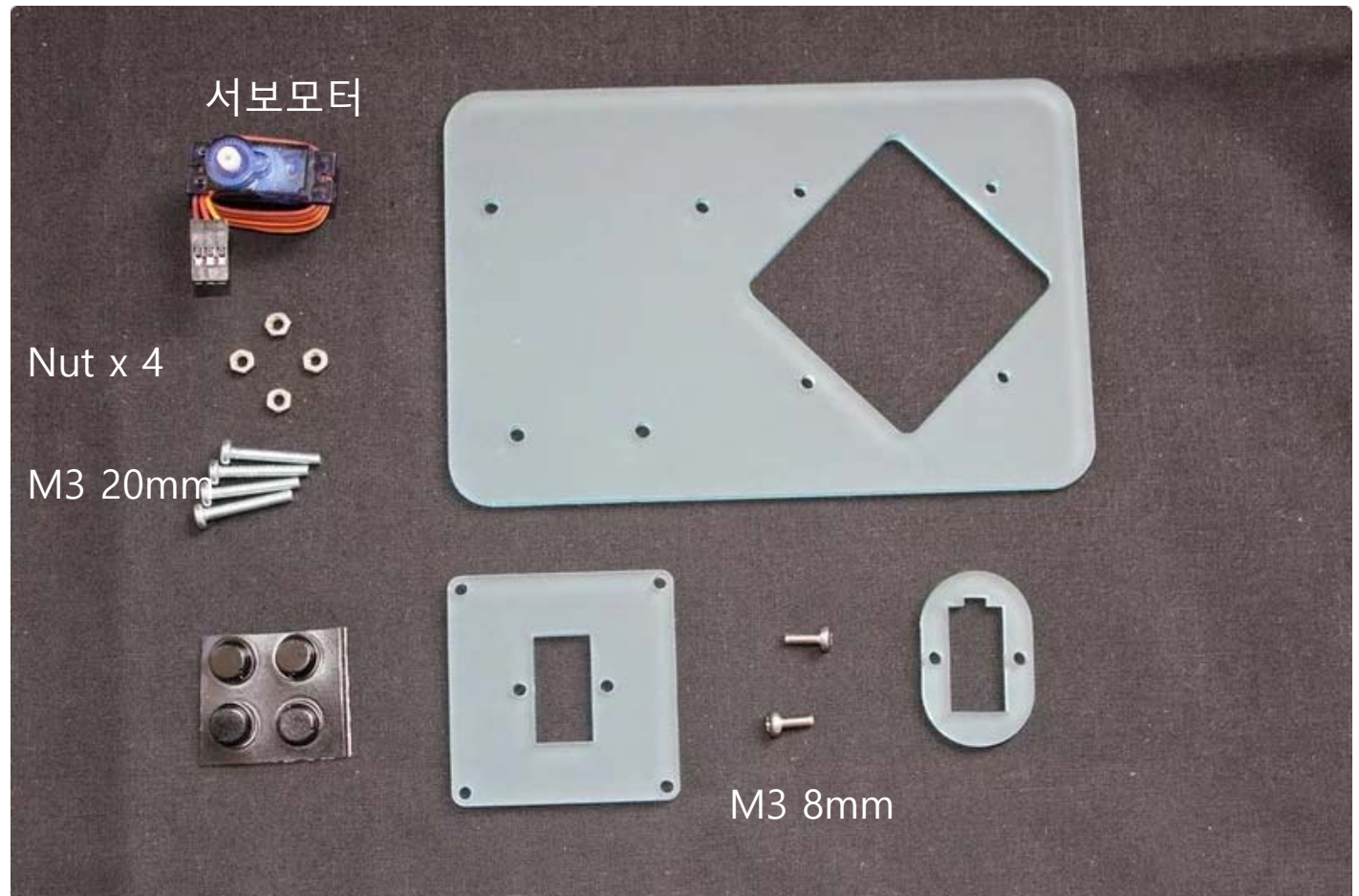
## 서보모터

servo x 4

## 과정 1\_베이스 조립

### 필요부품

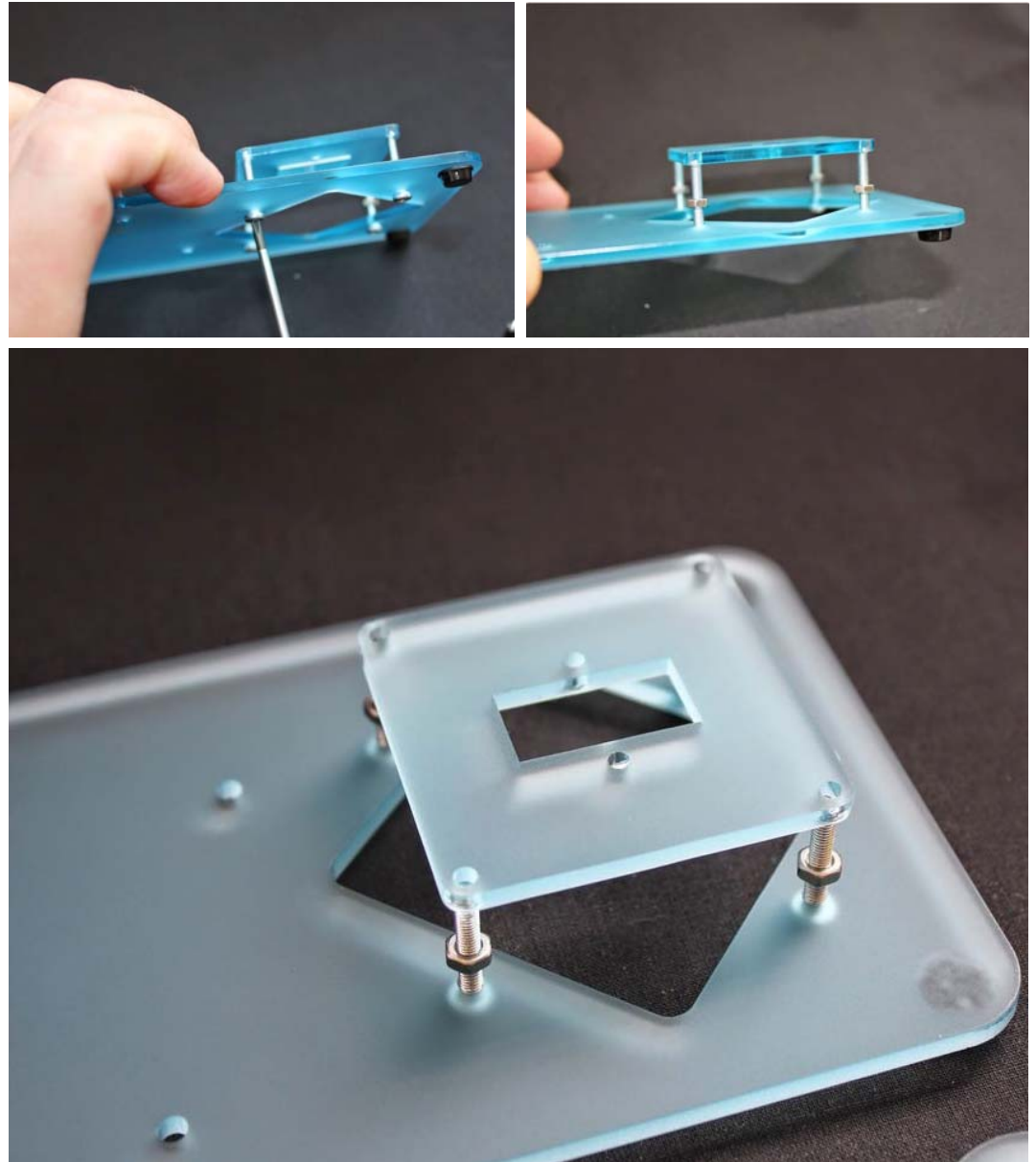
1. MDF
2. 서보모터
3. M3 20mm x 4
4. M3 8mm x 2
5. Nut x 4



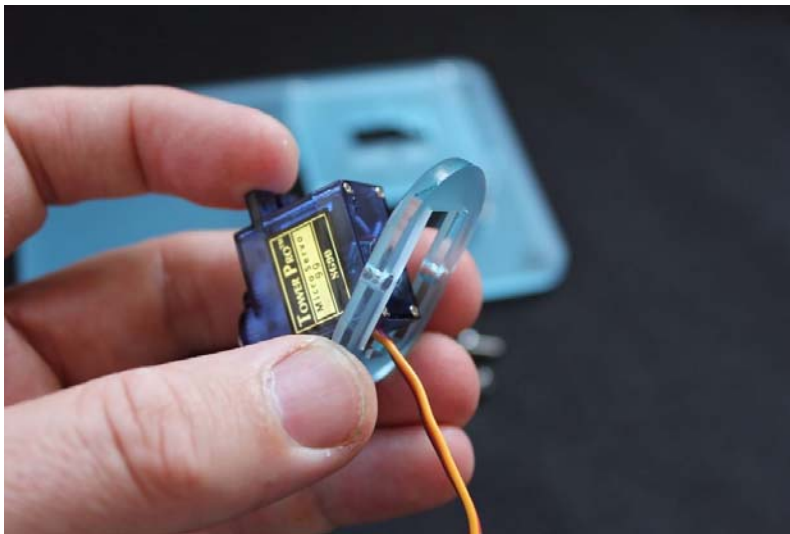
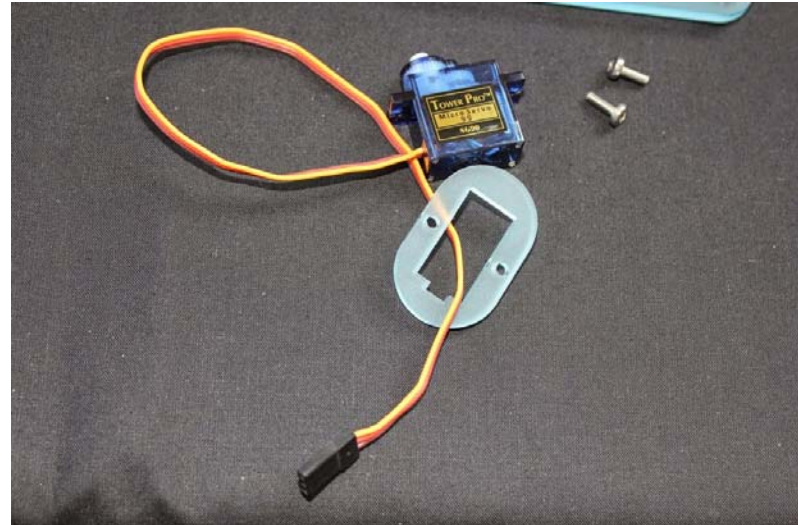
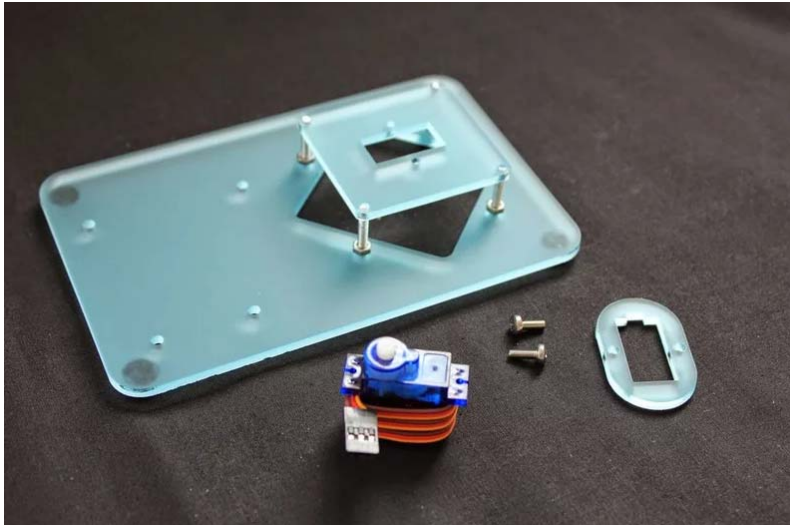


## 과정 1\_1 베이스 조립

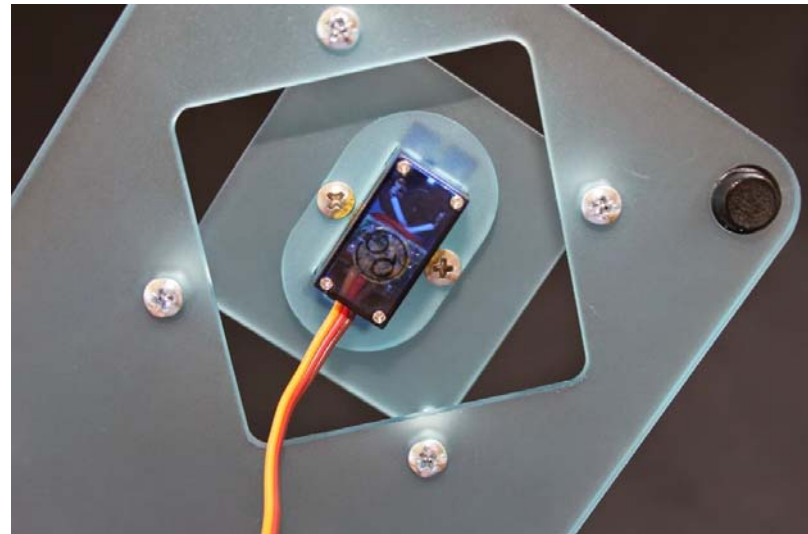
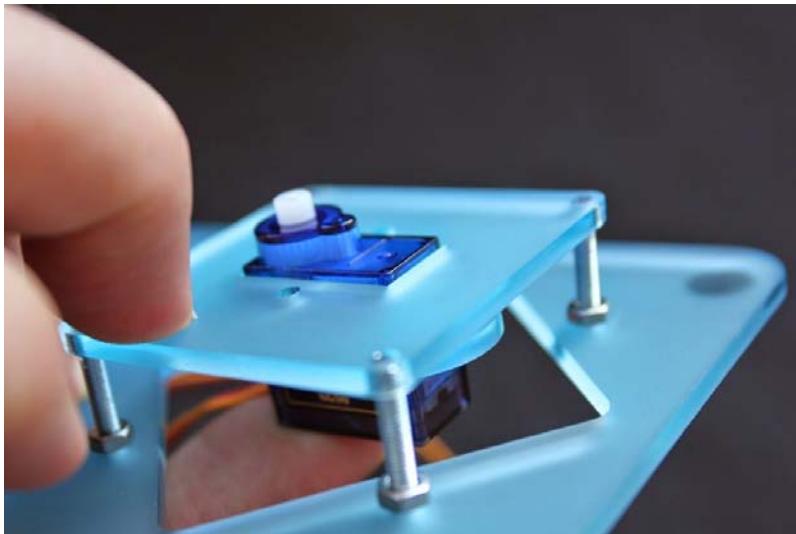
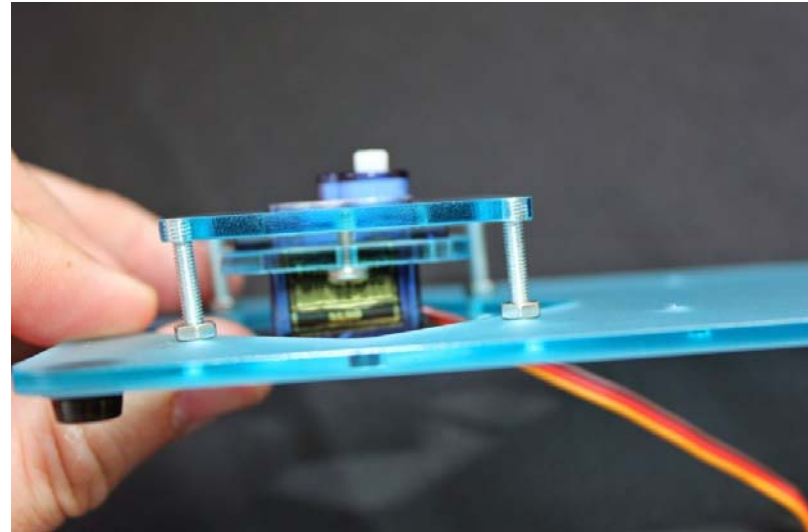
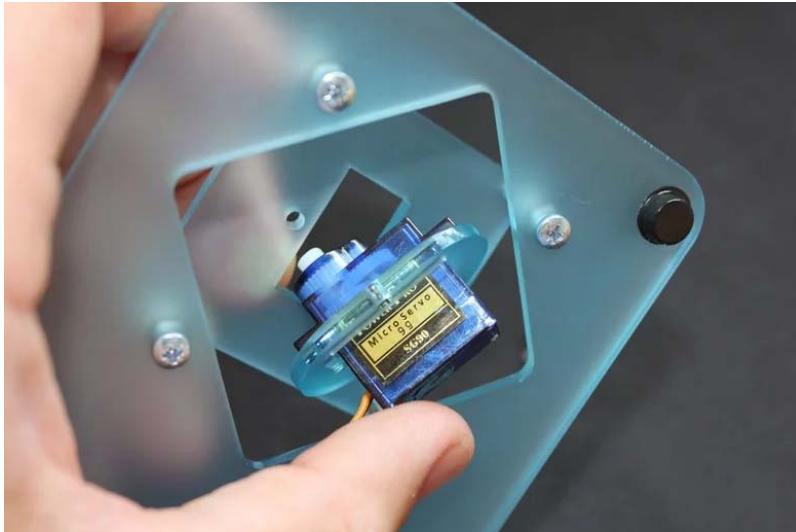
M3 20mm x4 와  
Nut x 4  
MDF 를 그림과 같이 조립합니다.



## 과정 1\_2 베이스 서보모터 조립



## 과정 1\_2 베이스 서보모터 조립

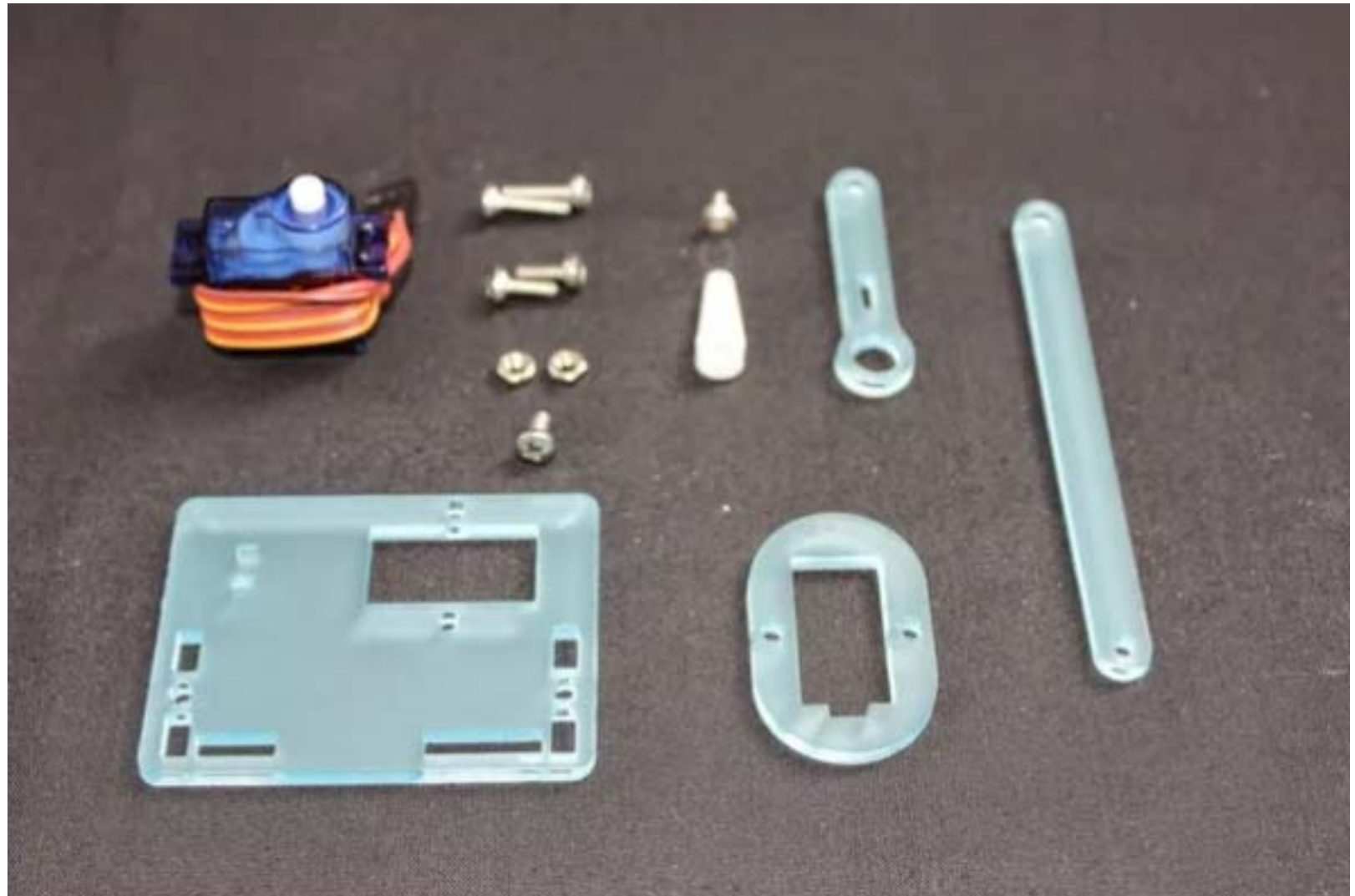




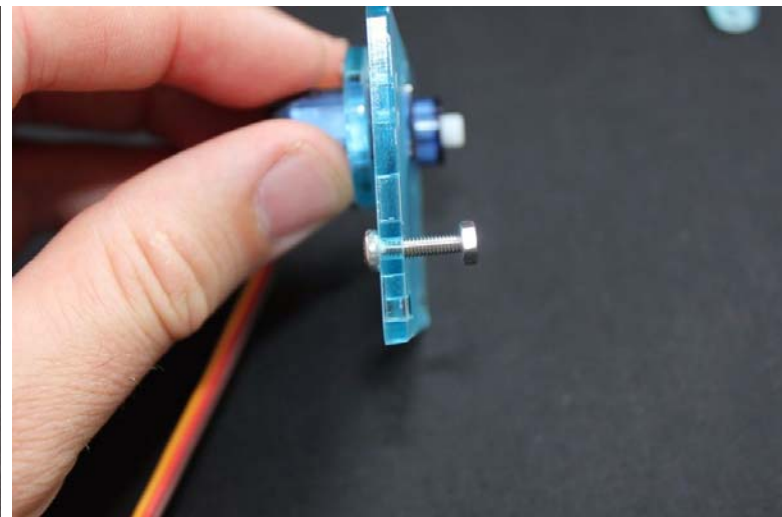
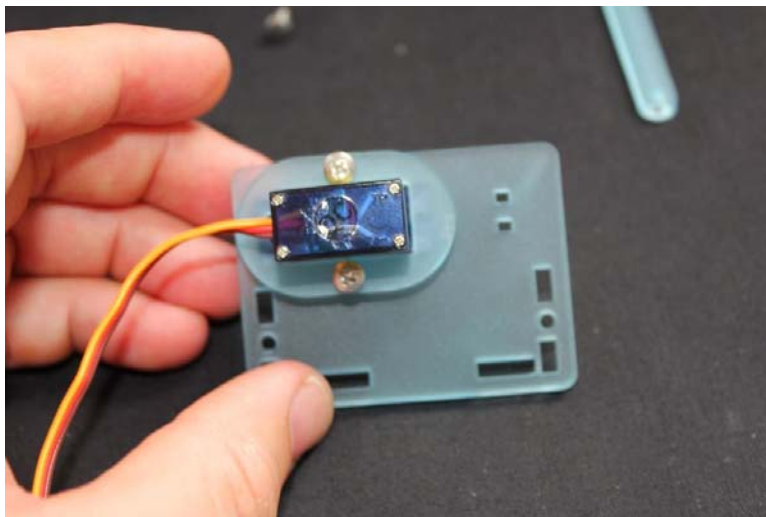
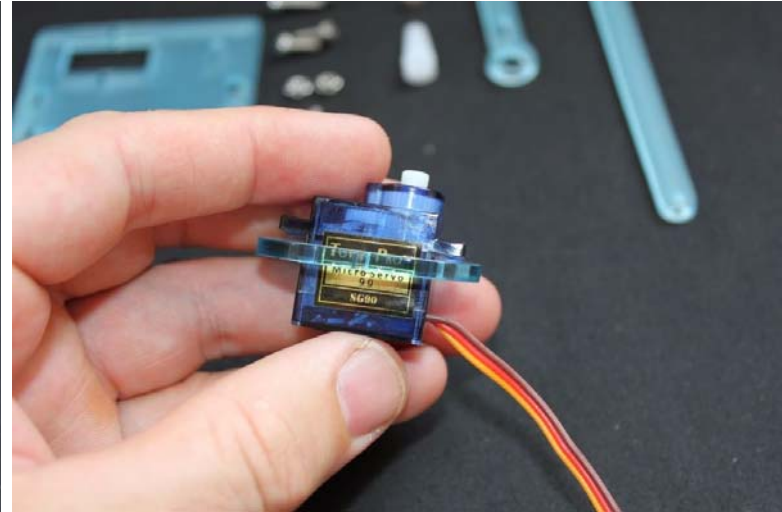
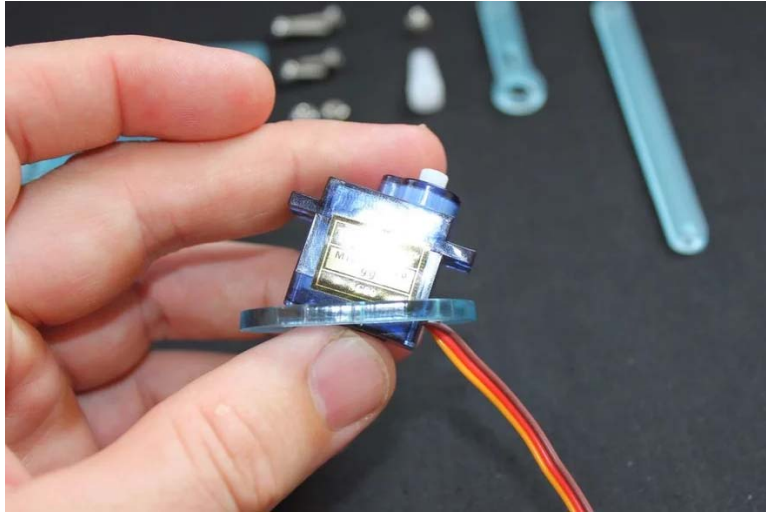
## 과정 2 바디 왼쪽 부분

### 필요부품

1. MDF
2. 서보모터
3. M3 8mm x 2
4. M3 12mm x 2
5. M3 6mm x 1
6. 서보모터 볼트 x 1
7. Nut x 2

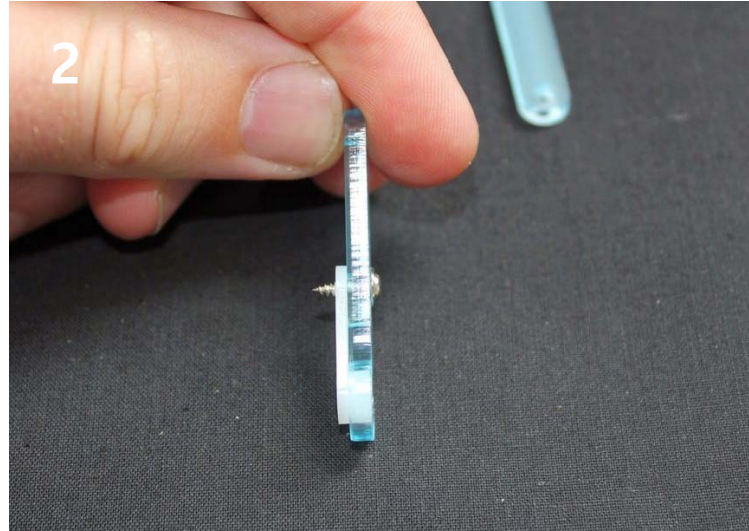


## 과정 2 바디 왼쪽 부분

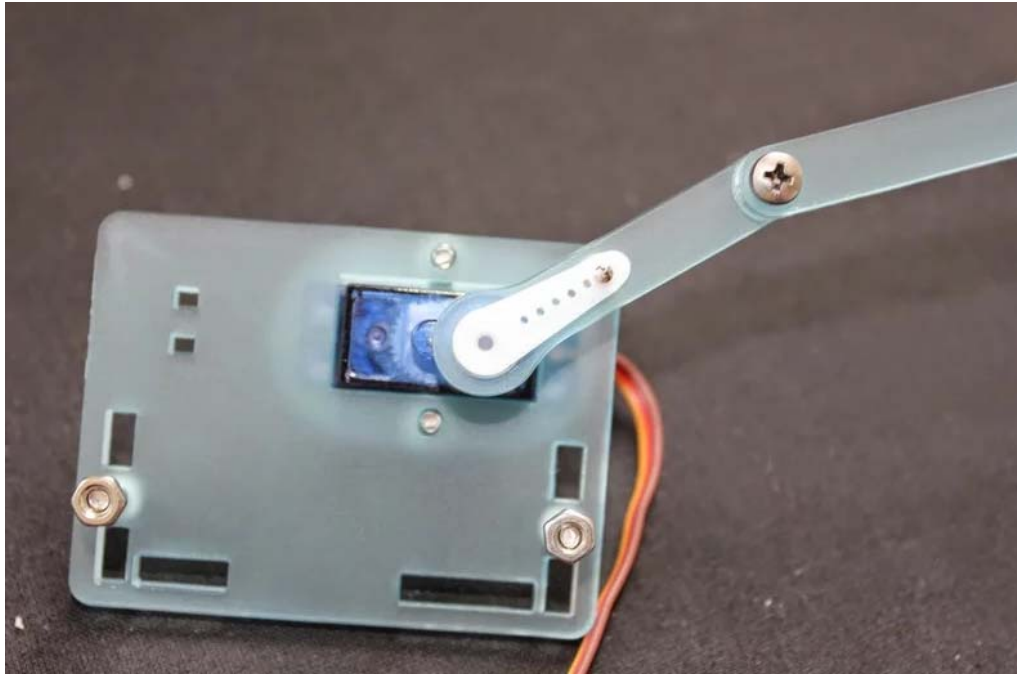




## 과정 2 바디 왼쪽 부분



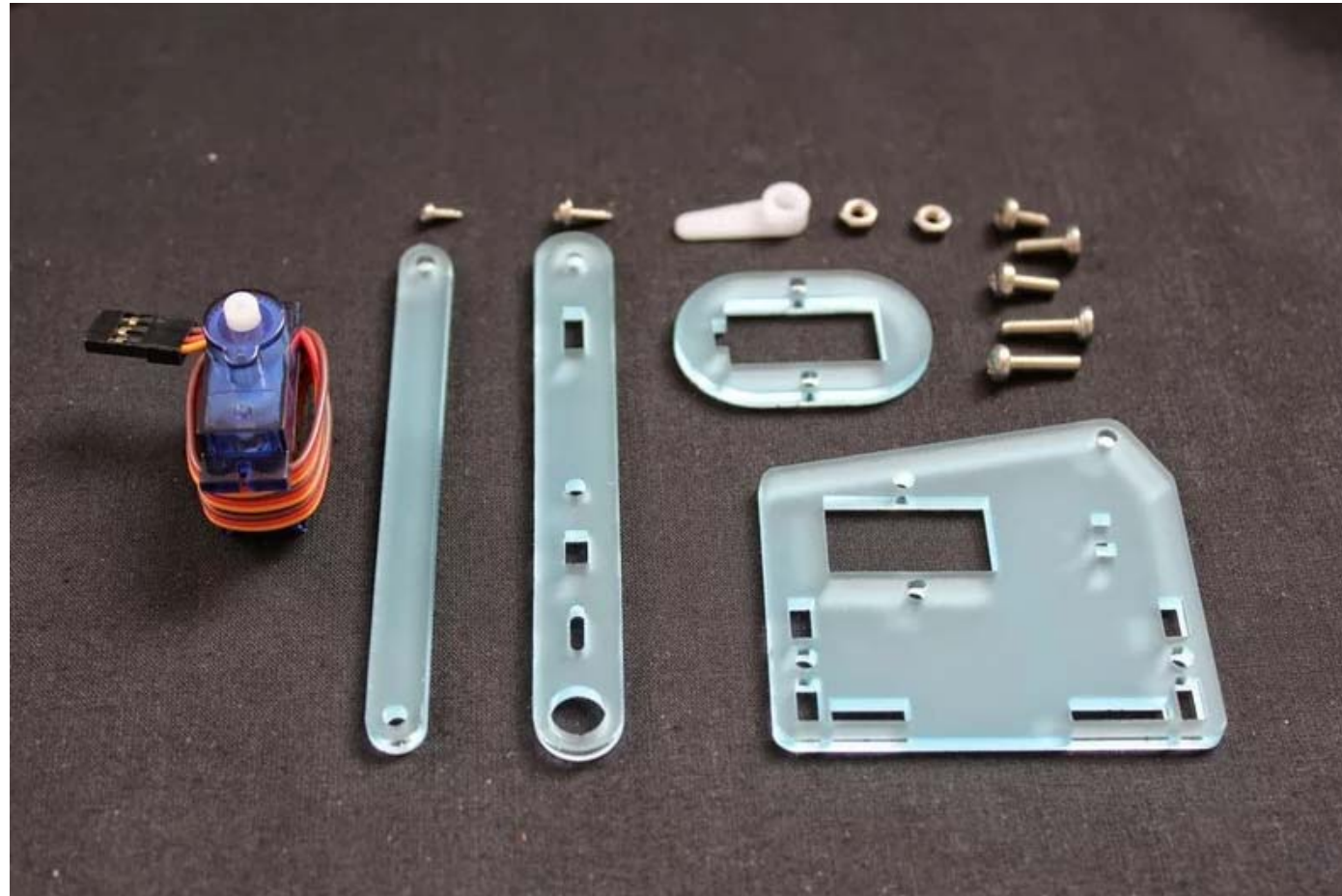
과정 2 바디 왼쪽 부분



과정 2 바디 오른쪽 부분

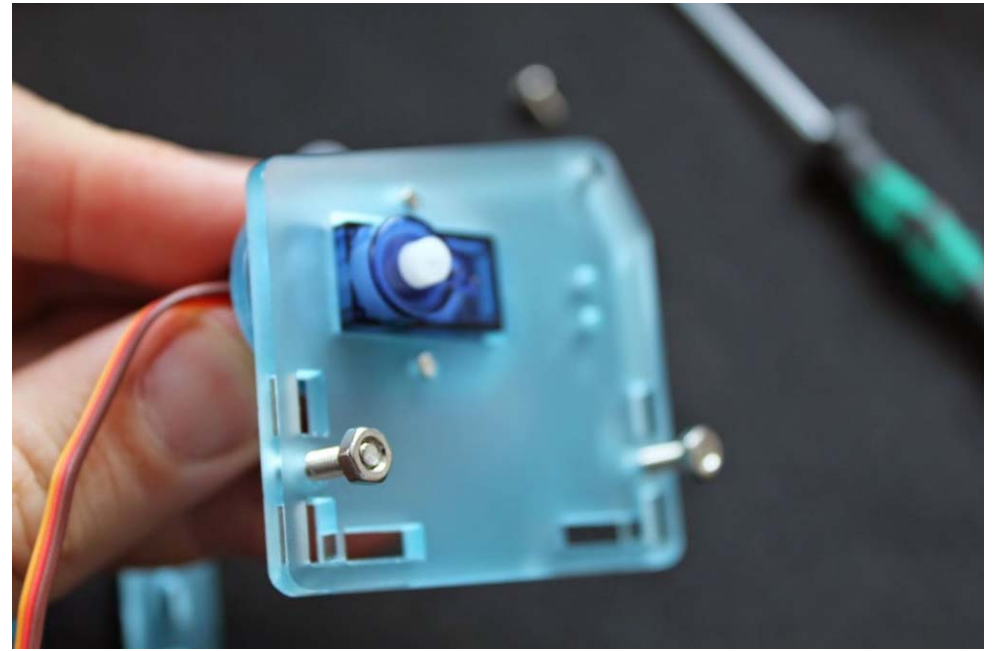
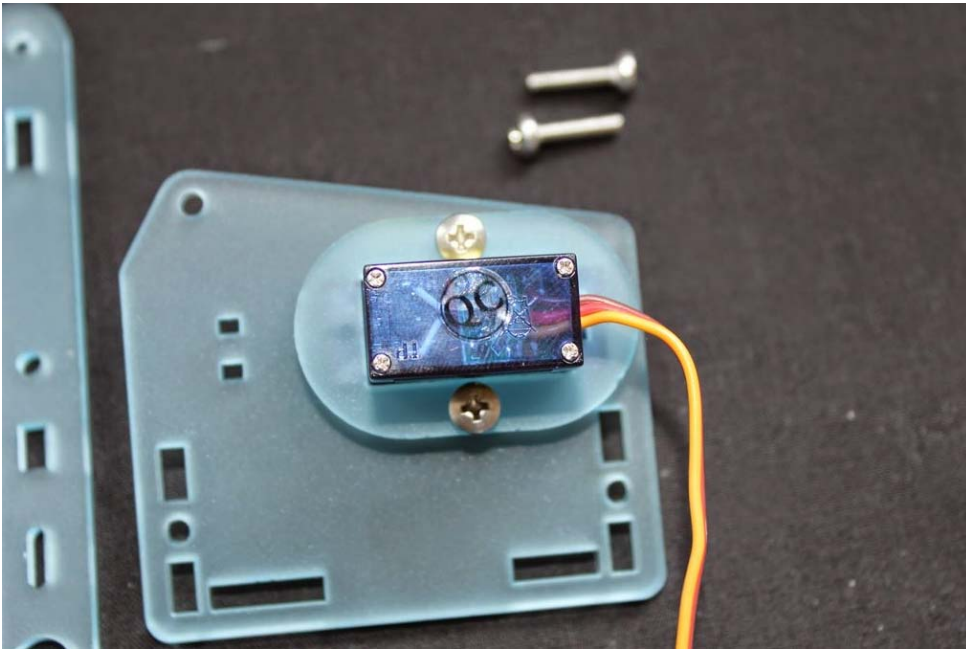
## 필요부품

1. MDF
2. 서보모터
3. M3 8mm x 2
4. M3 12mm x 2
5. M3 6mm x 1
6. 서보모터 볼트 x 1
7. Nut x 2

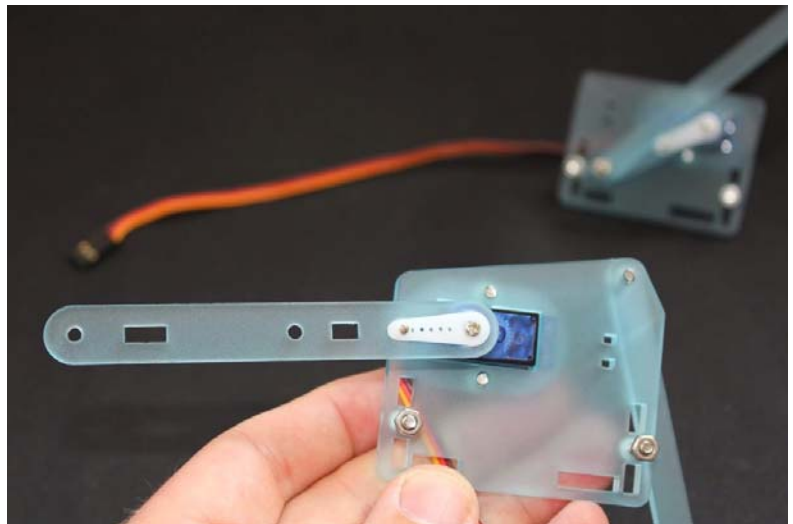
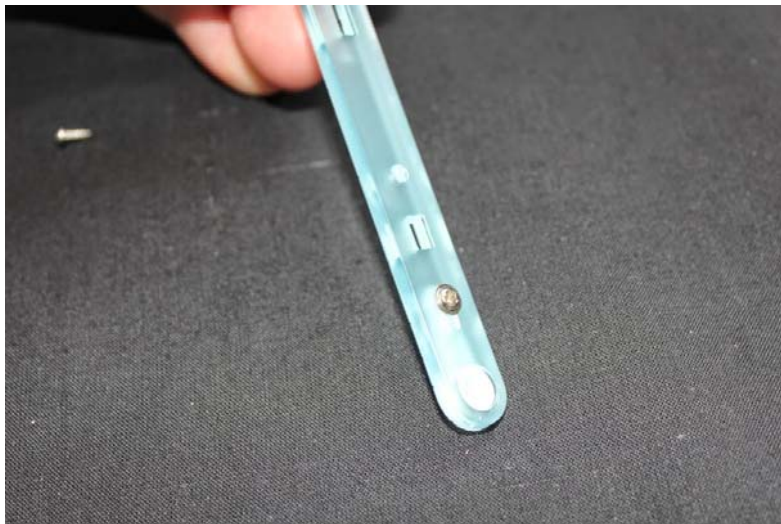
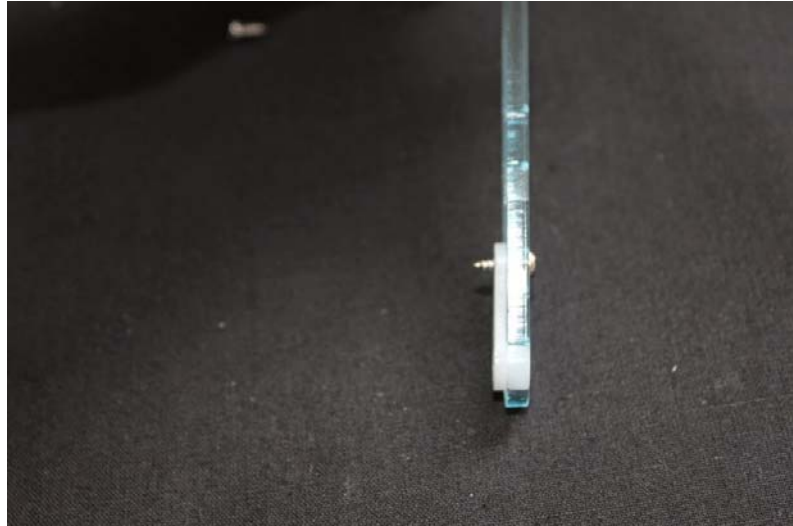




과정 2 바디 오른쪽 부분



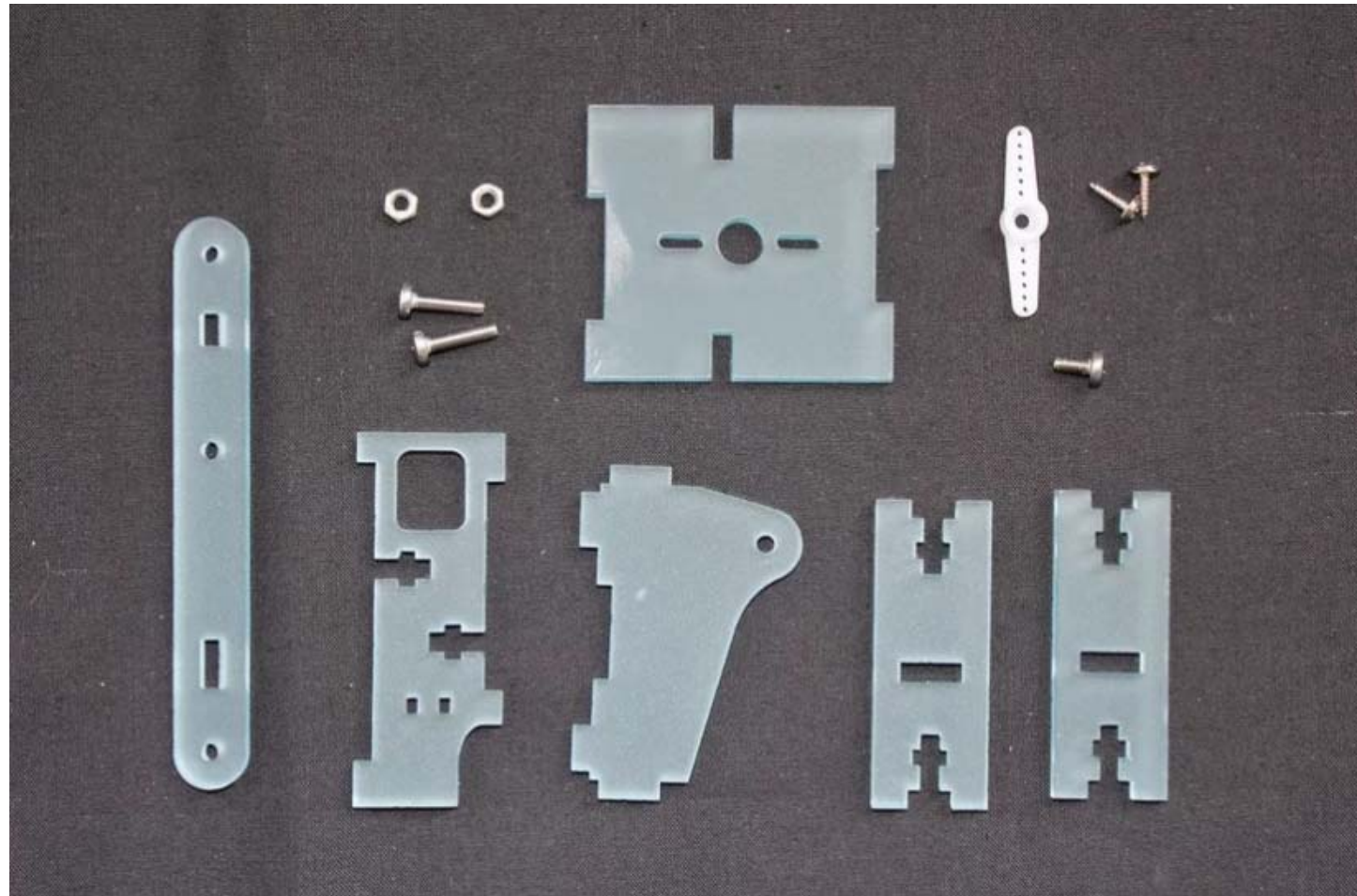
## 과정 2 바디 오른쪽 부분



### 과정 3 바디 종합 결함

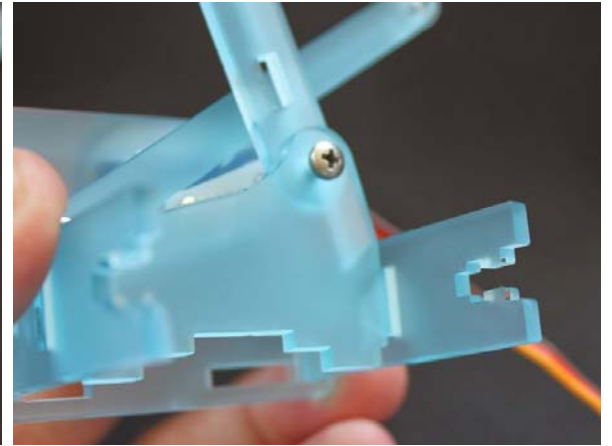
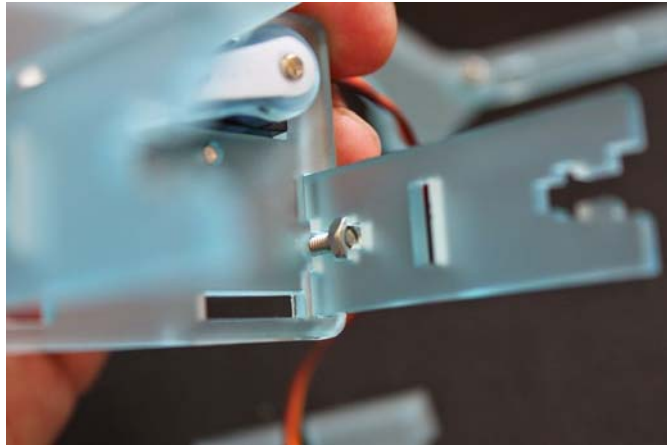
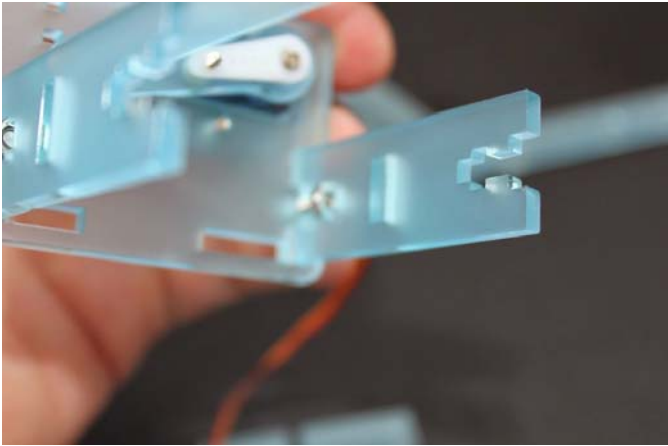
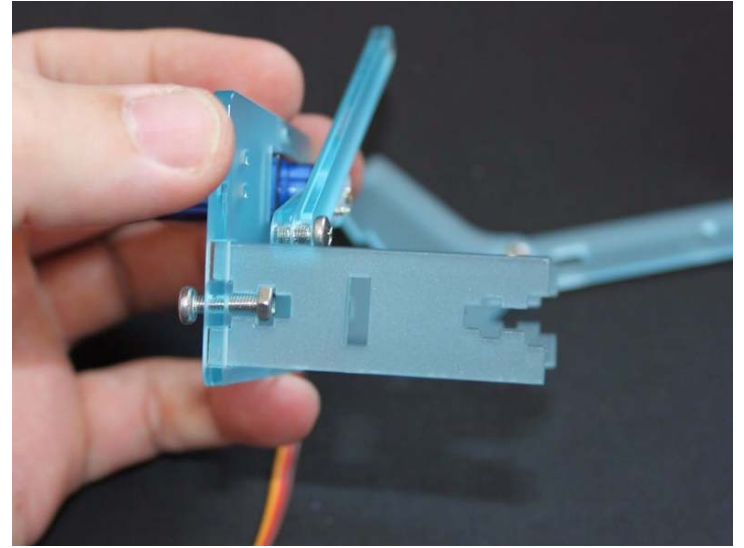
## 필요부품

1. MDF
2. M3 12mm x 2
3. M3 12mm x 2
4. M3 6mm x 1
5. Nut x 2
6. 서보모터 볼트

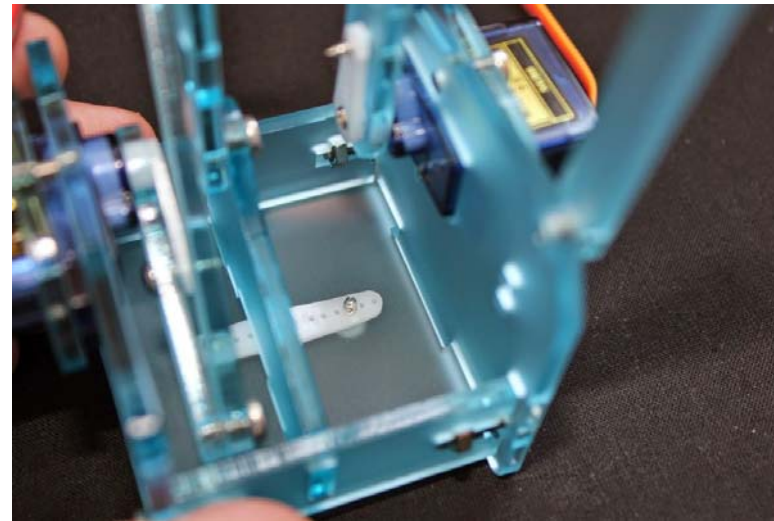
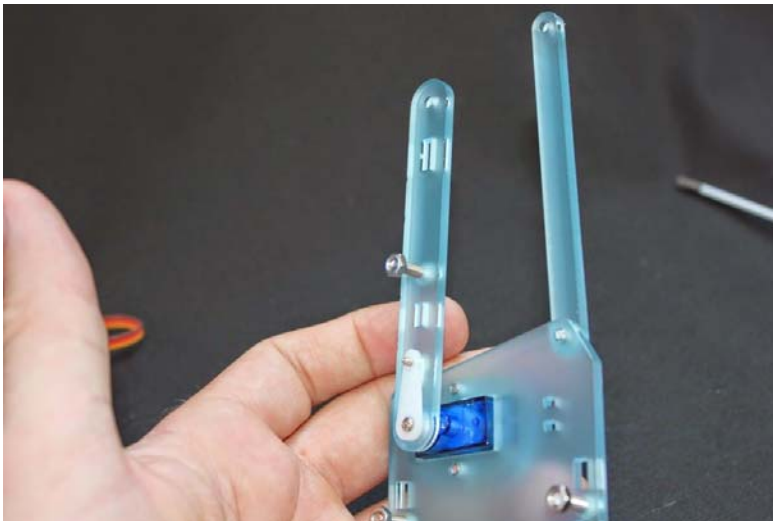
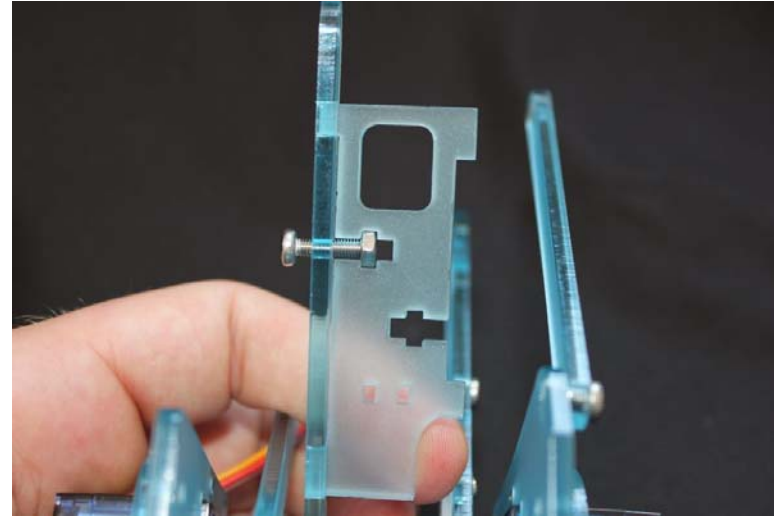
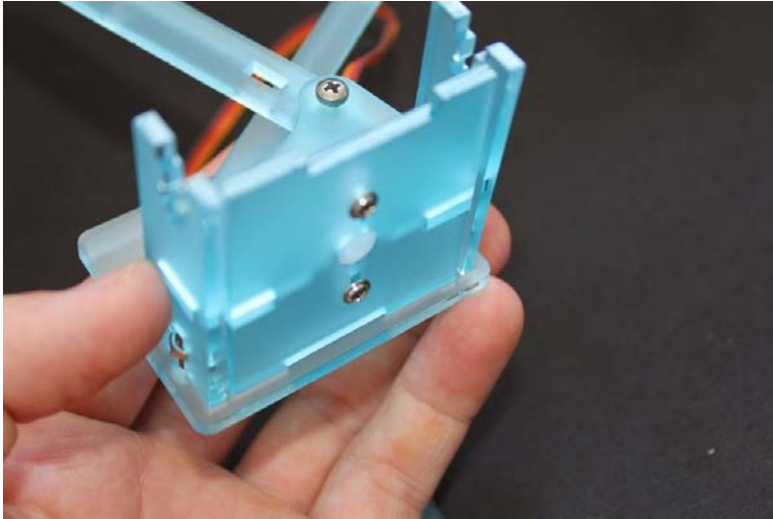




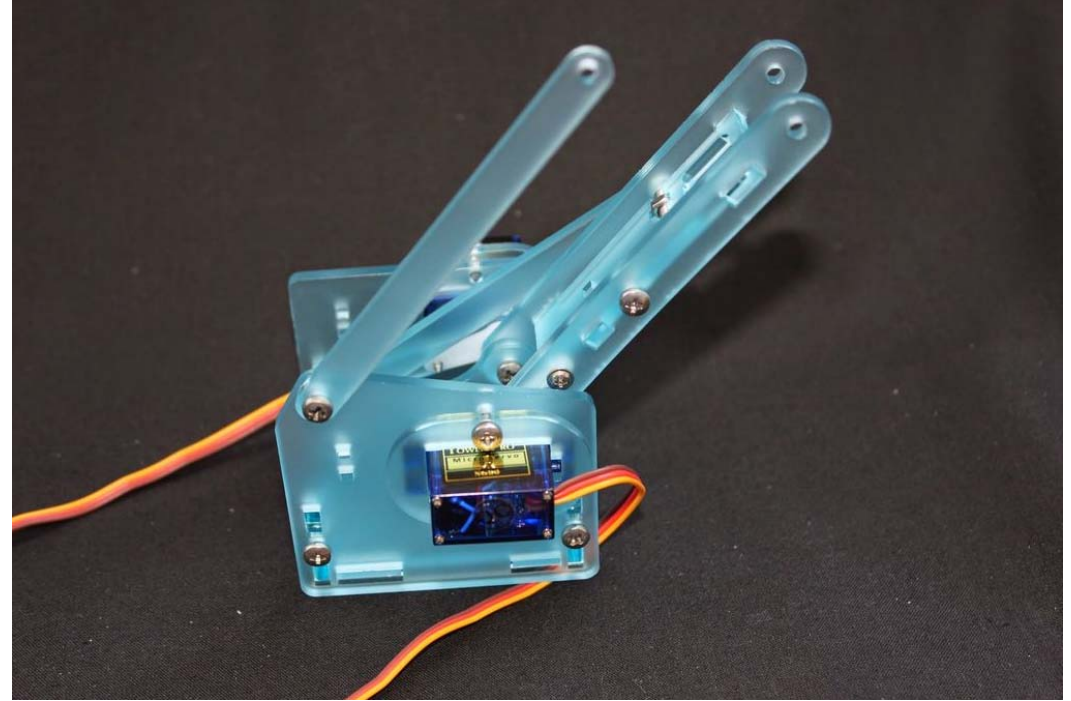
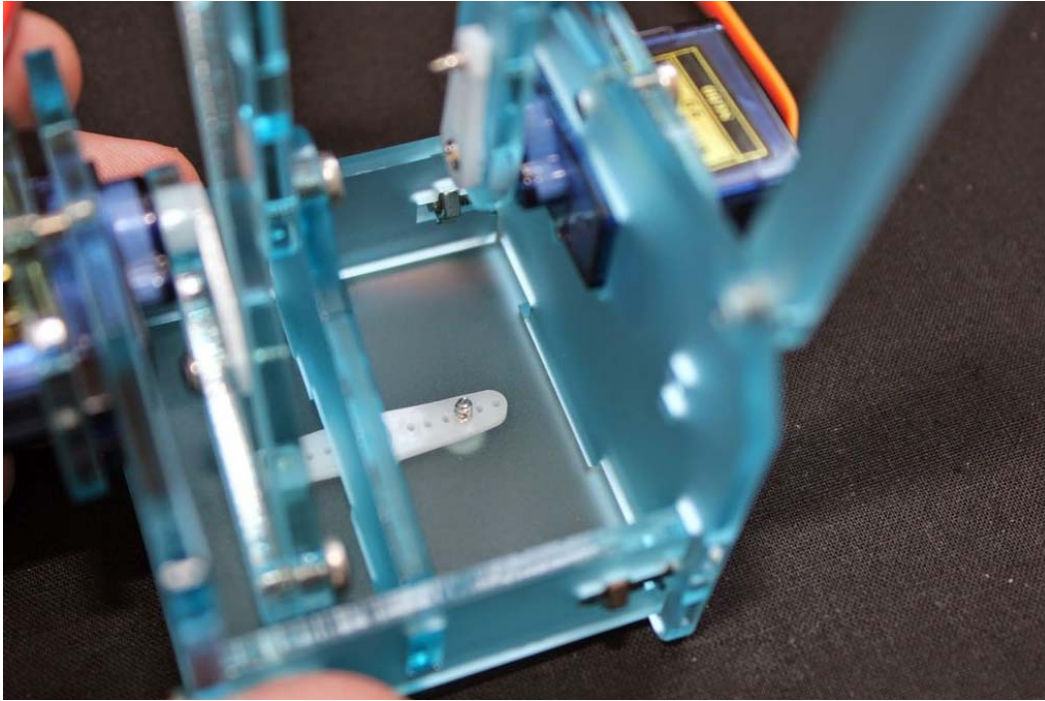
### 과정 3 바디 종합 결합



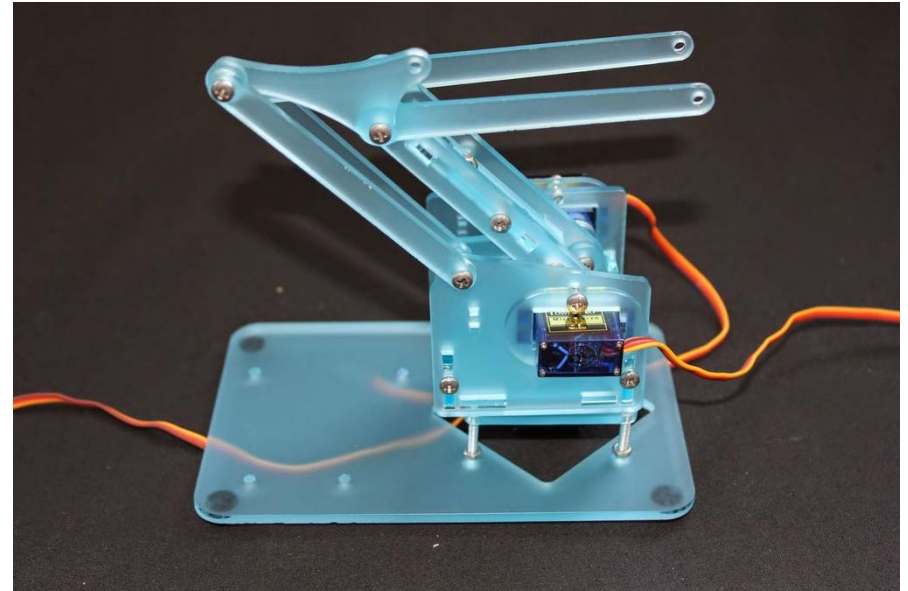
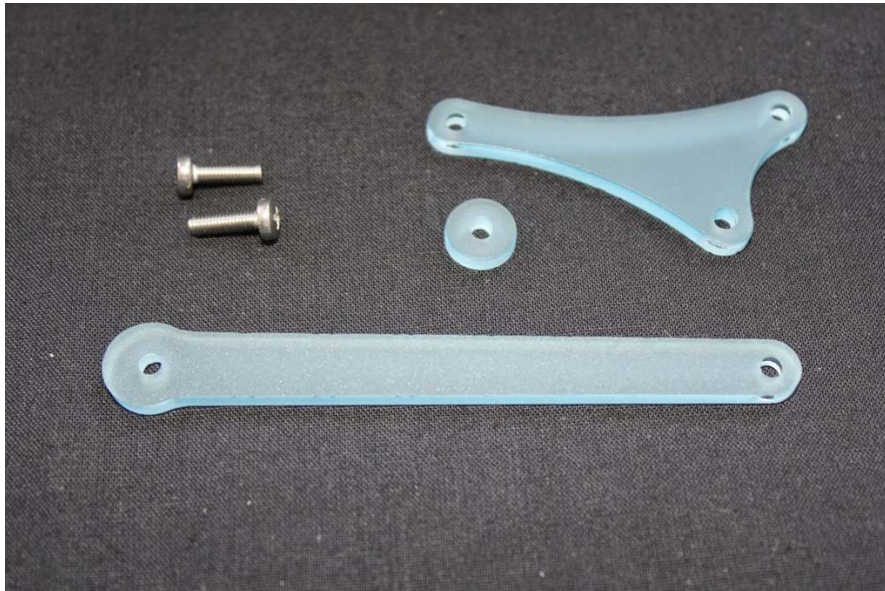
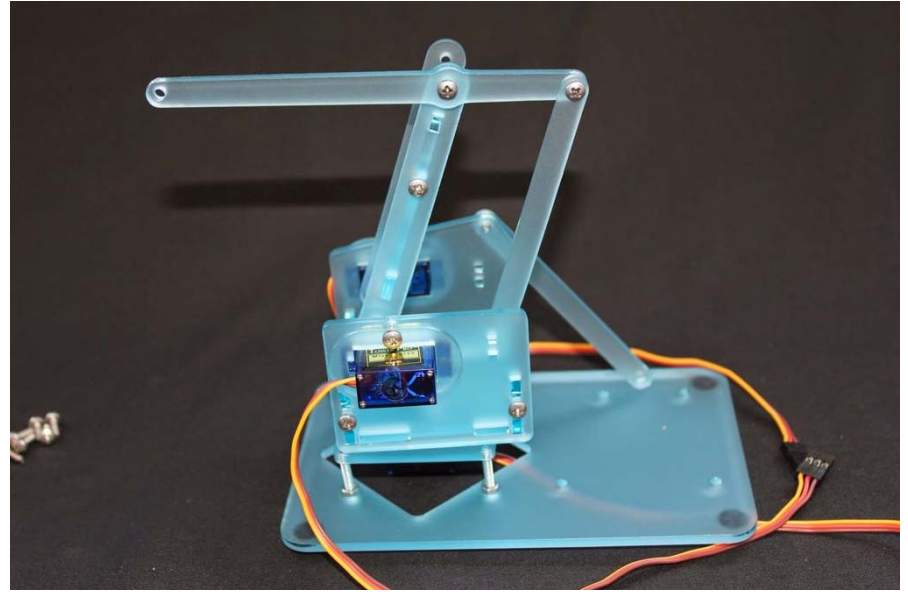
### 과정 3 바디 종합 결합

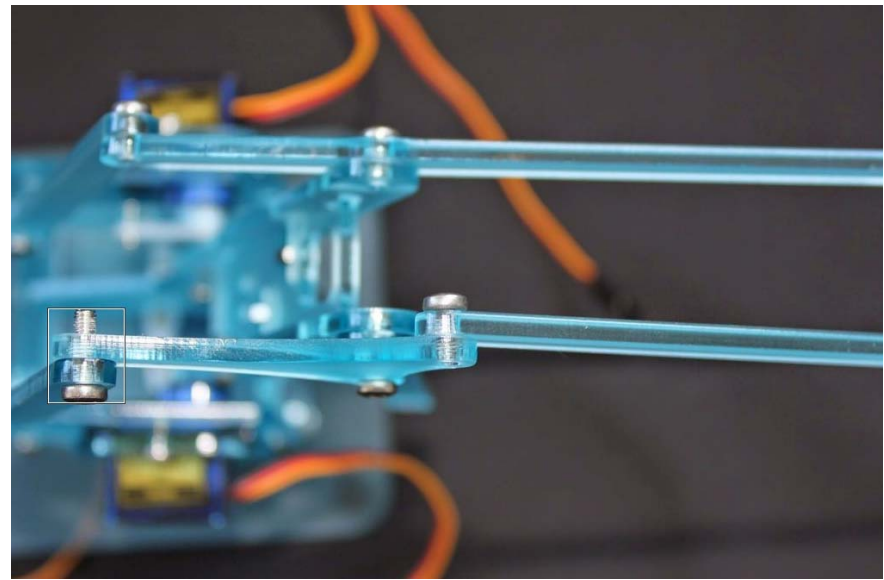
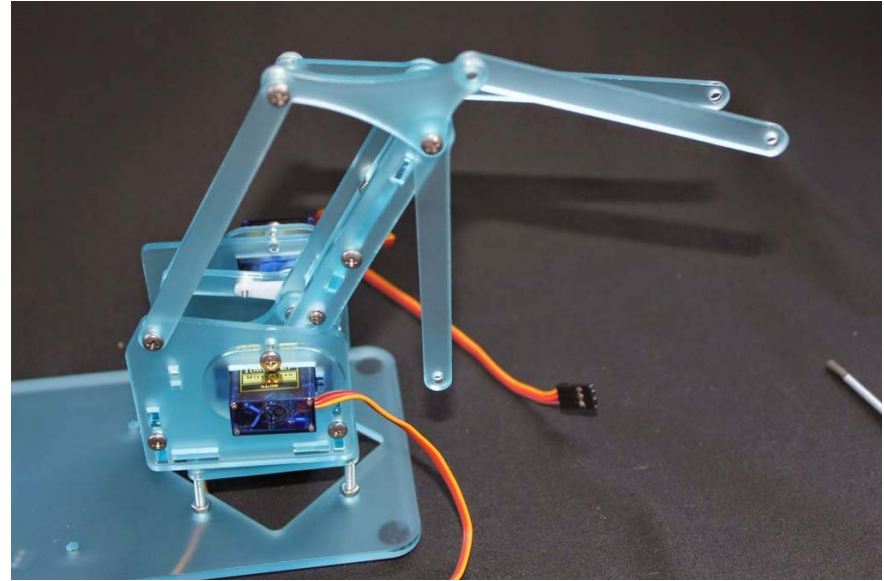
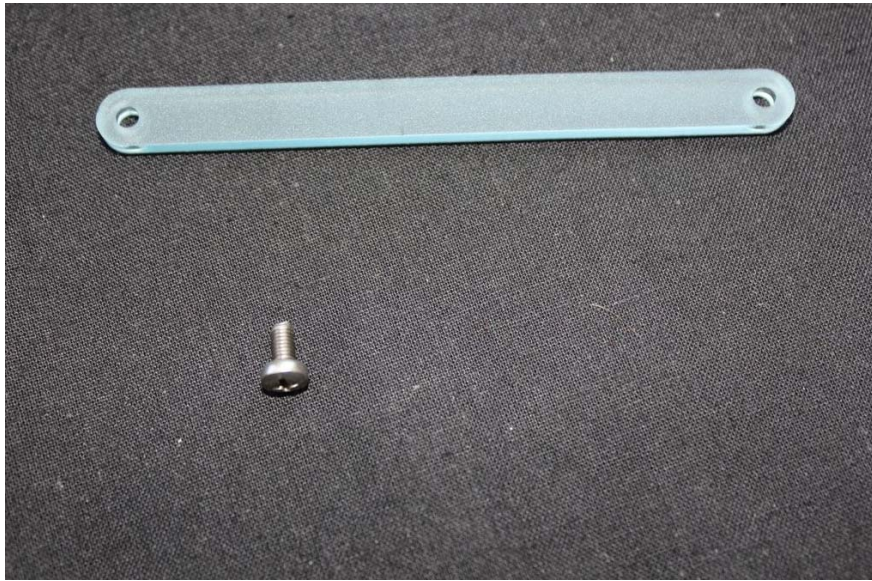


### 과정 3 바디 종합 결합







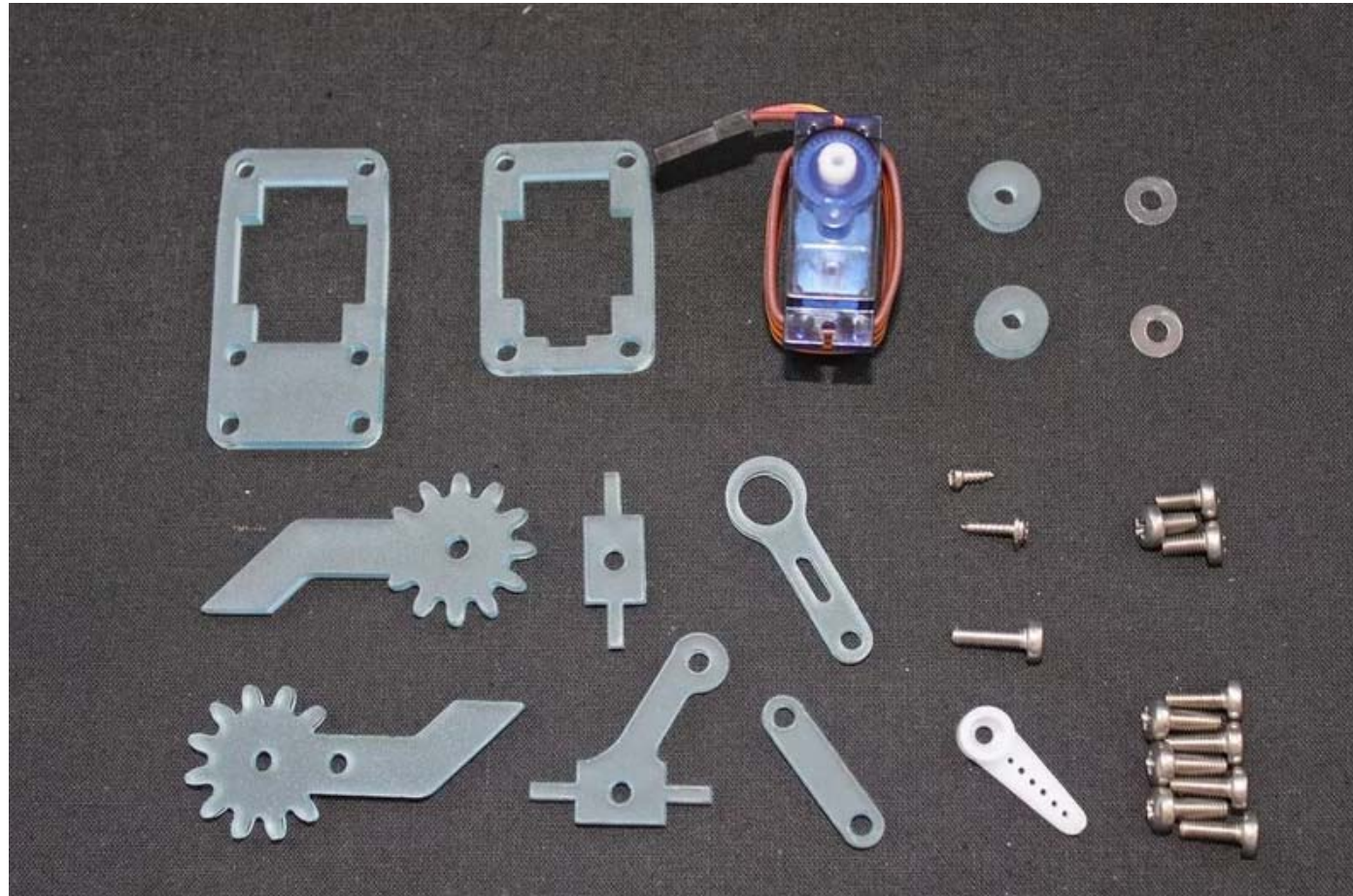




## 과정 5 그리퍼 조립

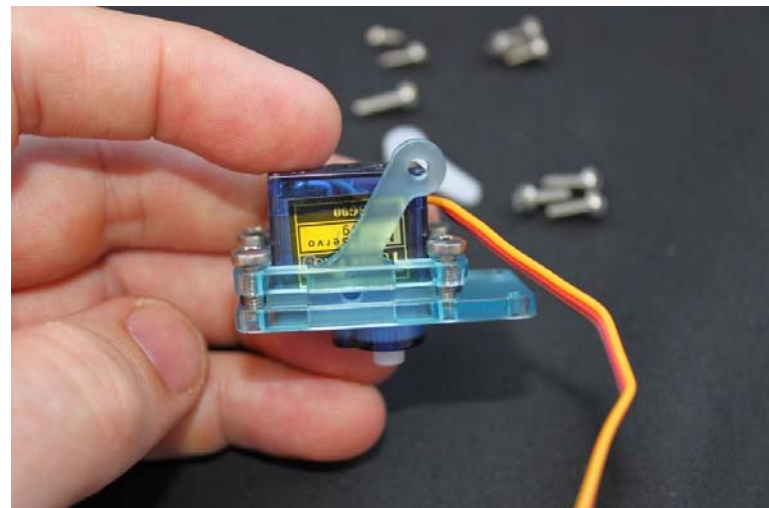
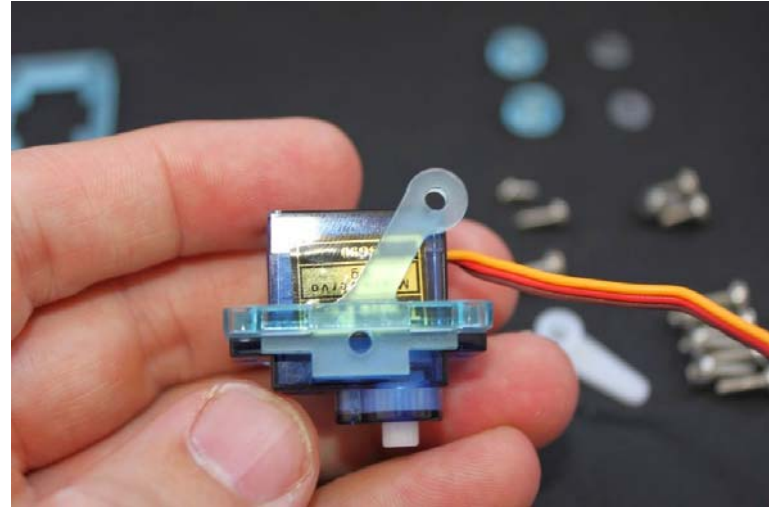
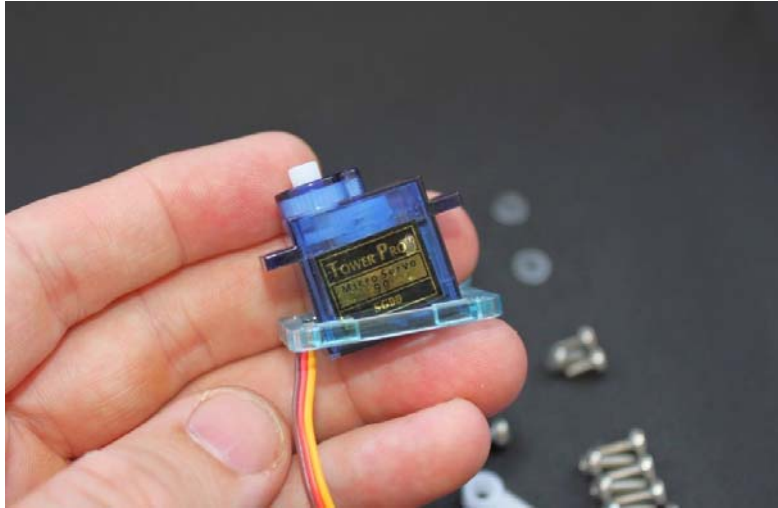
### 필요부품

1. MDF
2. 서보모터 x 1
3. M3 6mm x 3
4. M3 8mm x 7
5. M3 10mm x 1
6. Nut x 2
7. 서보모터 볼트

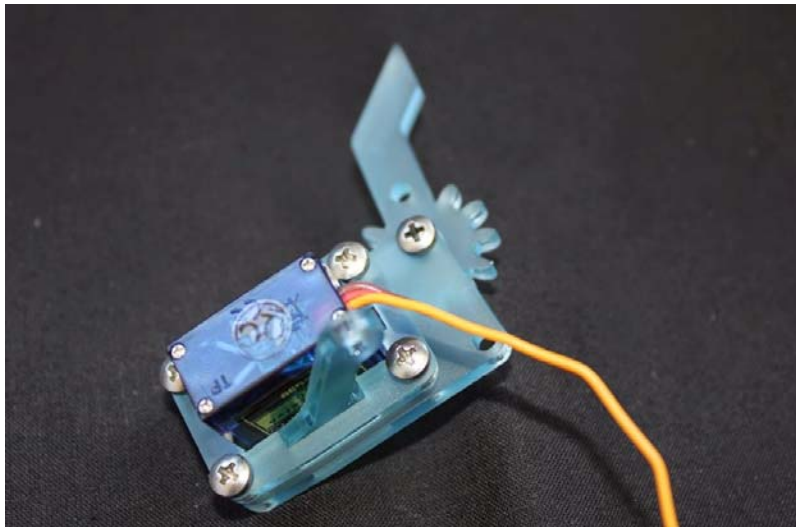
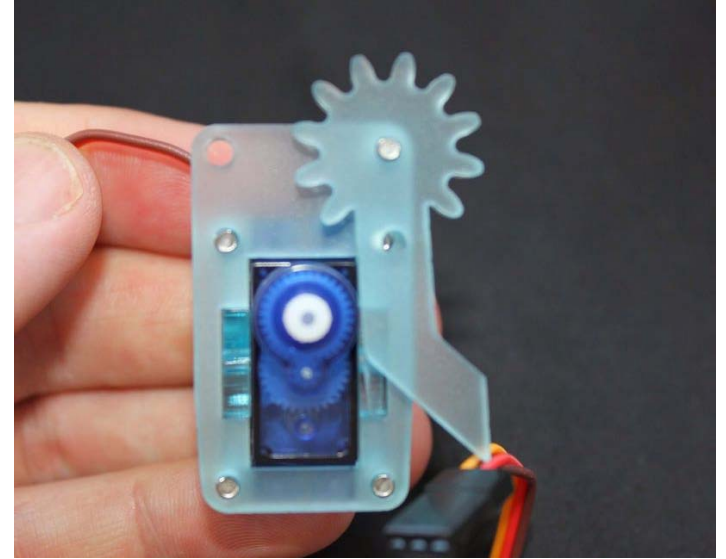
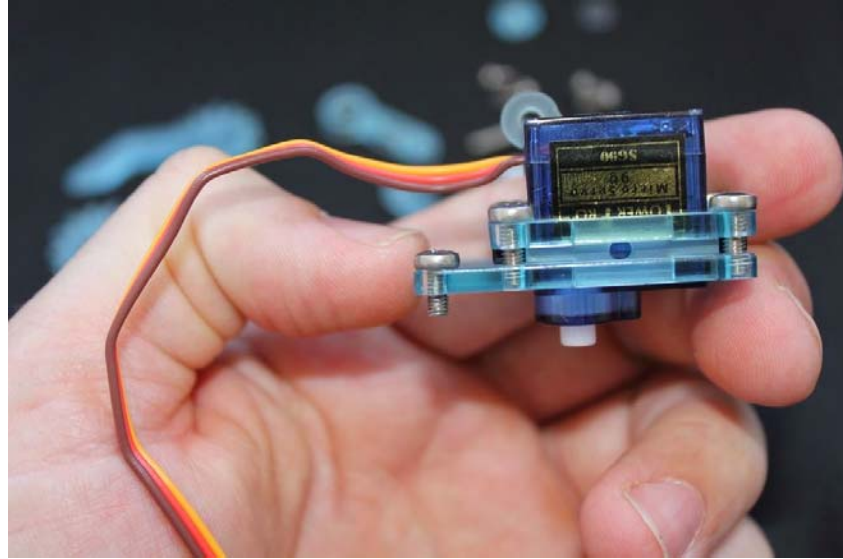
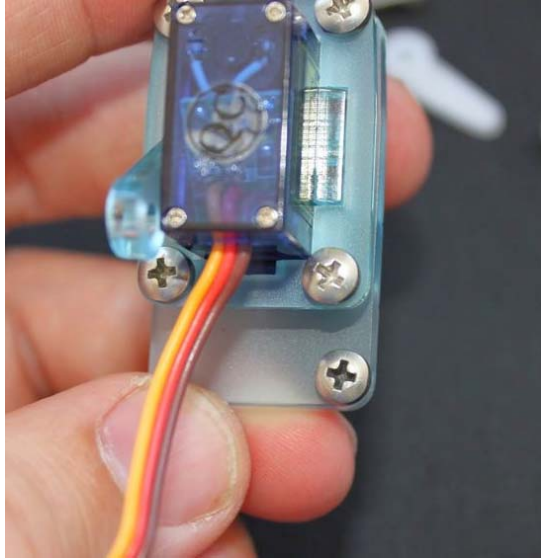




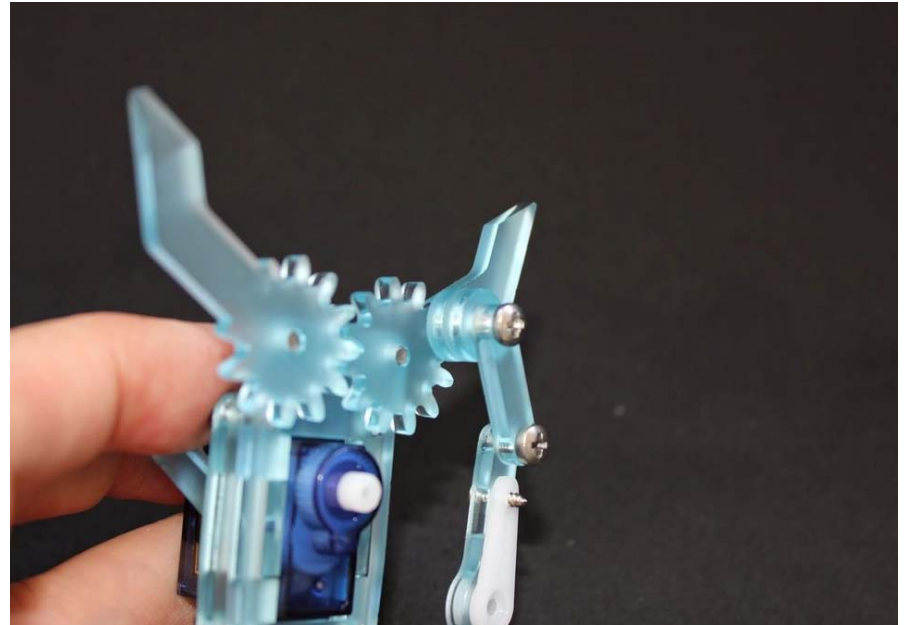
## 과정 5-1 그리퍼 조립



## 과정 5-2 그립퍼 조립



### 과정 5-3 그리퍼 조립





## 과정 5-4 Final

